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**King et al.**

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(54) **METHOD AND APPARATUS FOR MAKING STATUS REPORTING DEVICES FOR CONTAINER HANDLERS**

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#### Related U.S. Application Data

(63) Continuation of application No. 13/355,377, filed on Jan. 20, 2012, now Pat. No. 8,525,671, which is a continuation of application No. 12/574,624, filed on Oct. 6, 2009, now Pat. No. 8,188,865, which is a continuation of application No. 11/130,822, filed on May 16, 2005, now Pat. No. 7,598,863.

(60) Provisional application No. 60/571,009, filed on May 14, 2004.

(51) **Int. Cl.**  
**G08B 1/08** (2006.01)  
**B66C 13/48** (2006.01)

(Continued)

(52) **U.S. Cl.**

CPC ..... **G08C 17/02** (2013.01); **B65G 63/004** (2013.01); **B66C 13/46** (2013.01); **B66C 13/48** (2013.01); **B66C 19/002** (2013.01); **B66C 19/007** (2013.01); **B66F 9/065** (2013.01); **B66F 9/24** (2013.01); **G06Q 10/08** (2013.01); **G07C 3/00** (2013.01)

(58) **Field of Classification Search**

CPC ..... G08C 17/00; G08C 17/02; G08C 19/00; B65G 63/004; B66C 19/002; B66C 13/48; B66C 13/46; B66C 19/007; G08B 1/08  
USPC ..... 340/572.1, 539.1, 539.16, 539.17, 340/825.49, 825.69, 988, 539.19, 539.13; 235/375, 383, 385, 380, 381; 700/213, 700/214, 229; 701/207, 208, 209; 705/1, 705/29, 35

See application file for complete search history.

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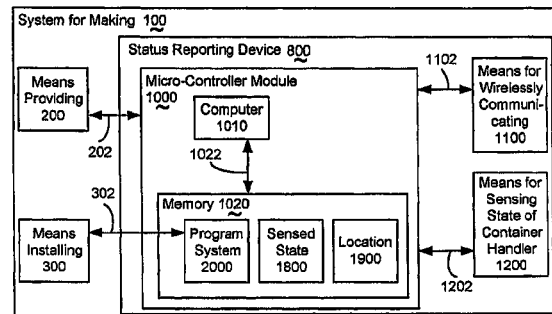
Primary Examiner — Hung T Nguyen

(74) Attorney, Agent, or Firm — Staniford Tomita LLP

(57) **ABSTRACT**

A mechanism and method for making status reporting devices for container handlers, including: providing a micro-controller module, and installing a program system into memory accessed by a computer directing the micro-controller module. The micro-controller module communicatively couples with means for wirelessly communicating and for sensing a state of the container handler. Means for wirelessly communicating may include means for wirelessly determining container handler location. The micro-controller module may be communicatively coupled to a separate means for determining location. An apparatus making the devices may include a second program system directing the invention's method through a second computer, which may control an assembly device in creating the micro-controller, coupled with the means for sensing and for wirelessly communicating.

**14 Claims, 31 Drawing Sheets**



(51) **Int. Cl.**

|                   |           |
|-------------------|-----------|
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| <b>B65G 63/00</b> | (2006.01) |
| <b>B66C 19/00</b> | (2006.01) |
| <b>B66F 9/065</b> | (2006.01) |
| <b>B66F 9/24</b>  | (2006.01) |
| <b>G06Q 10/08</b> | (2012.01) |
| <b>G07C 3/00</b>  | (2006.01) |
| <b>B66C 13/46</b> | (2006.01) |

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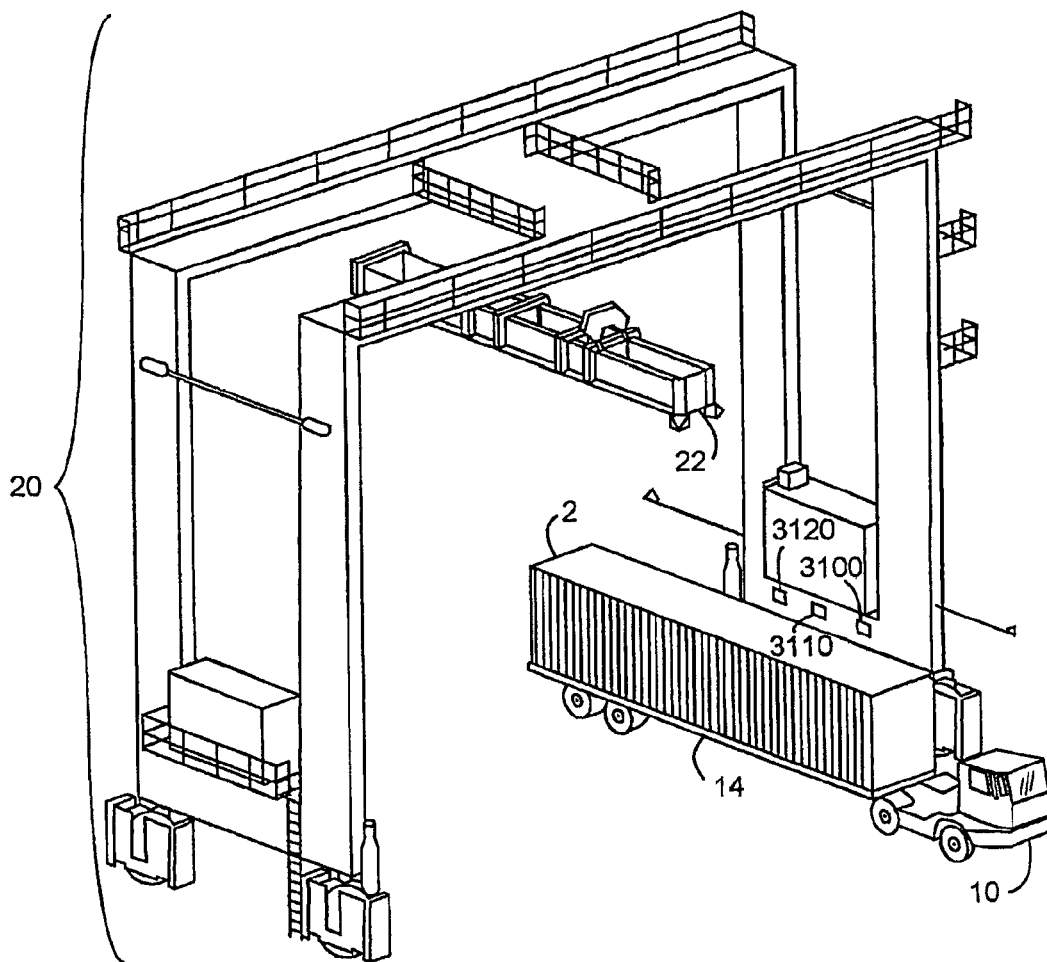


Fig. 1

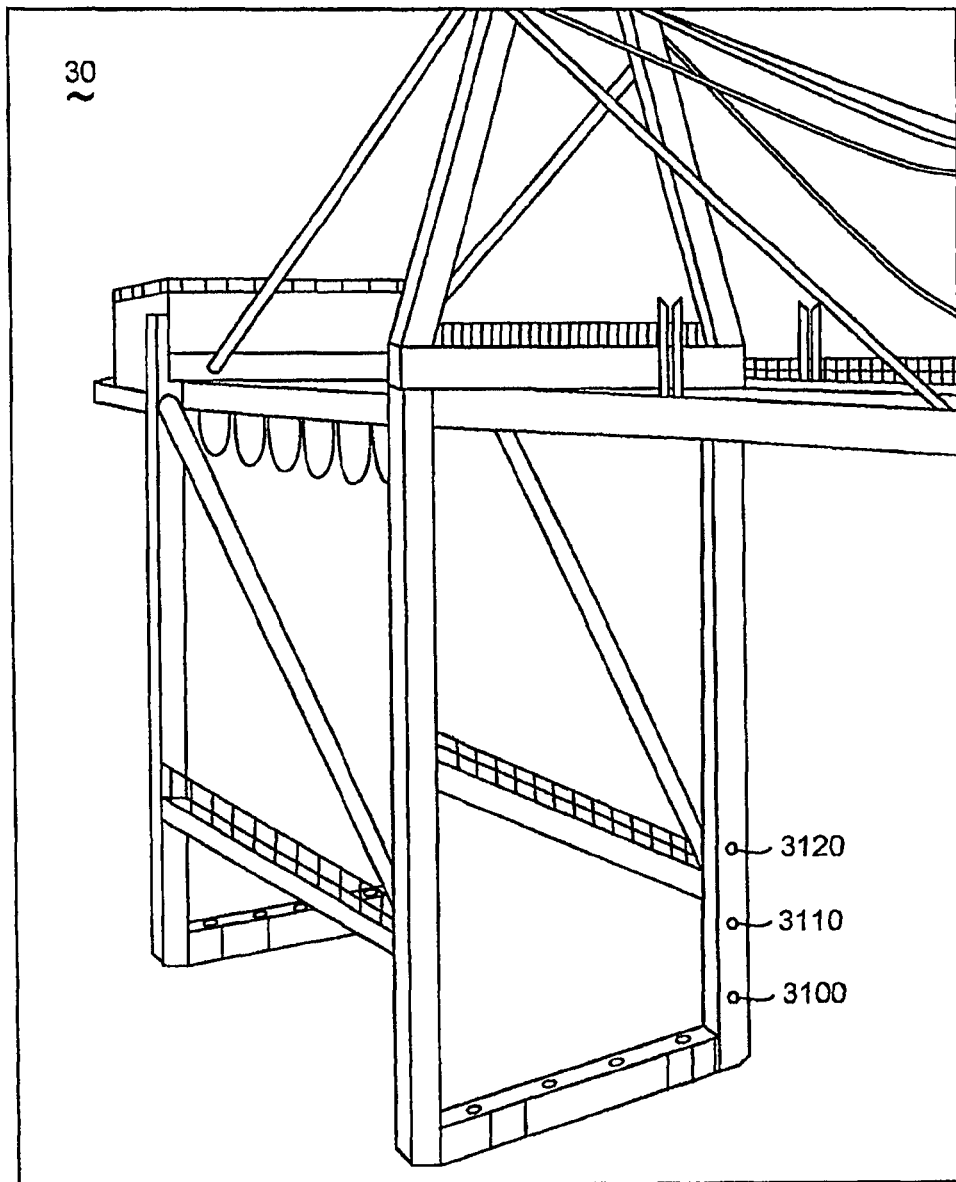


Fig. 2

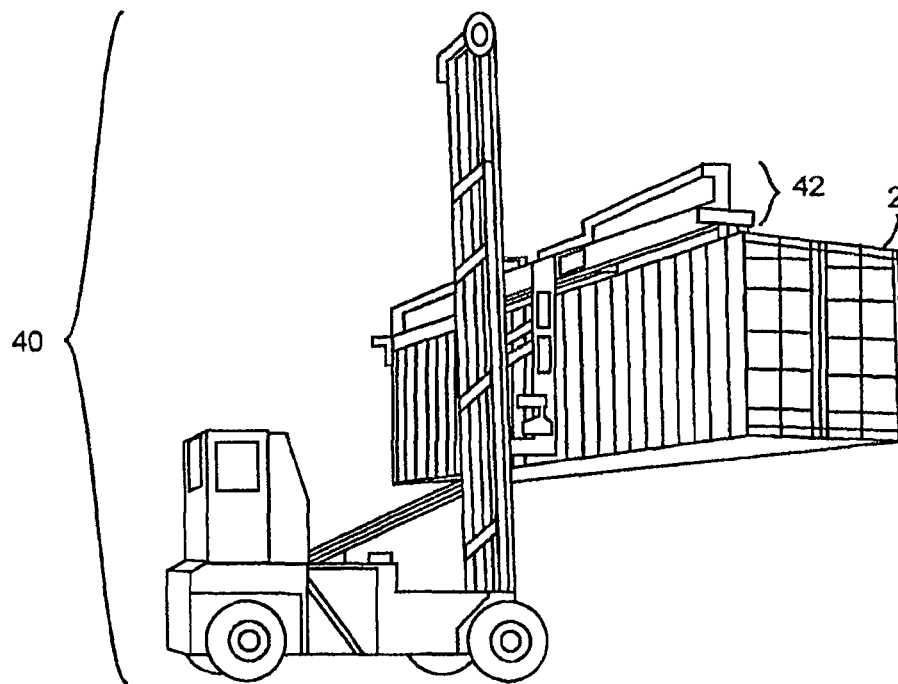


Fig. 3A

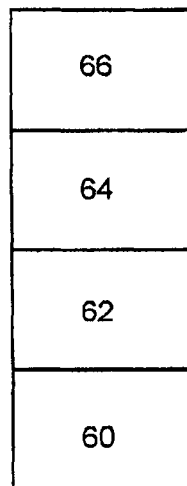


Fig. 3B

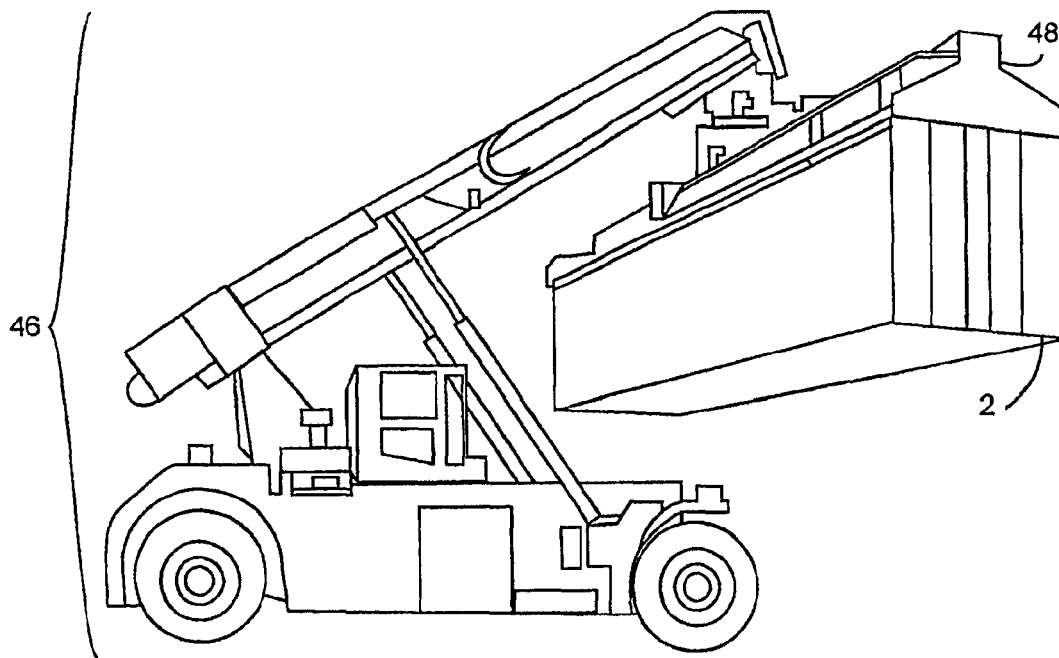


Fig. 4A

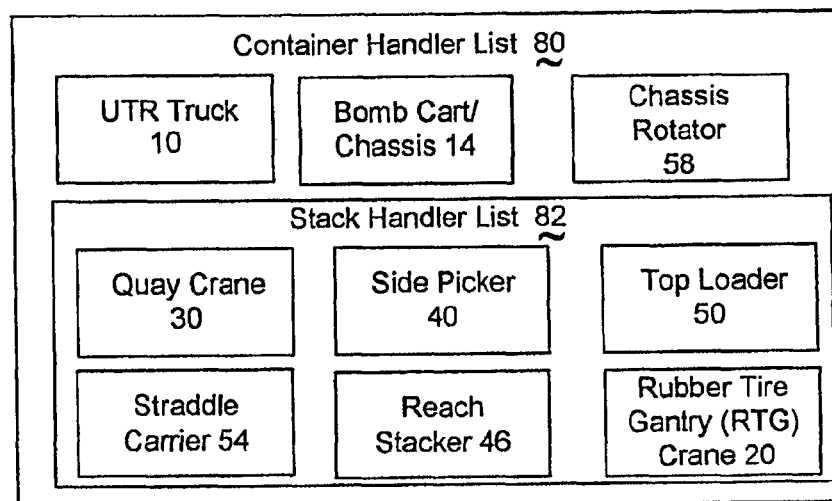


Fig. 4B

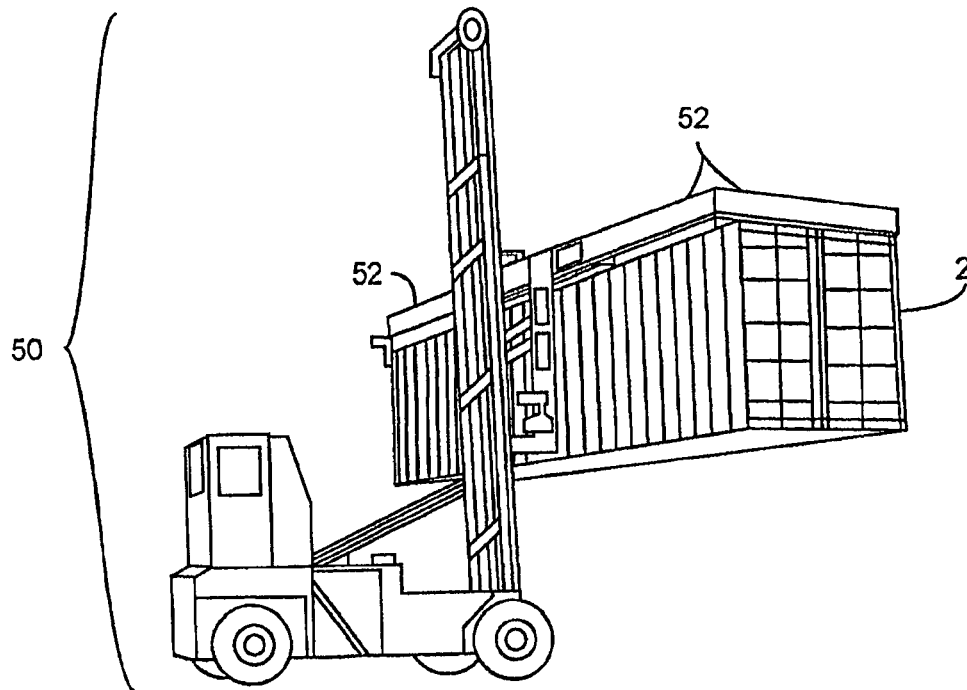


Fig. 4C

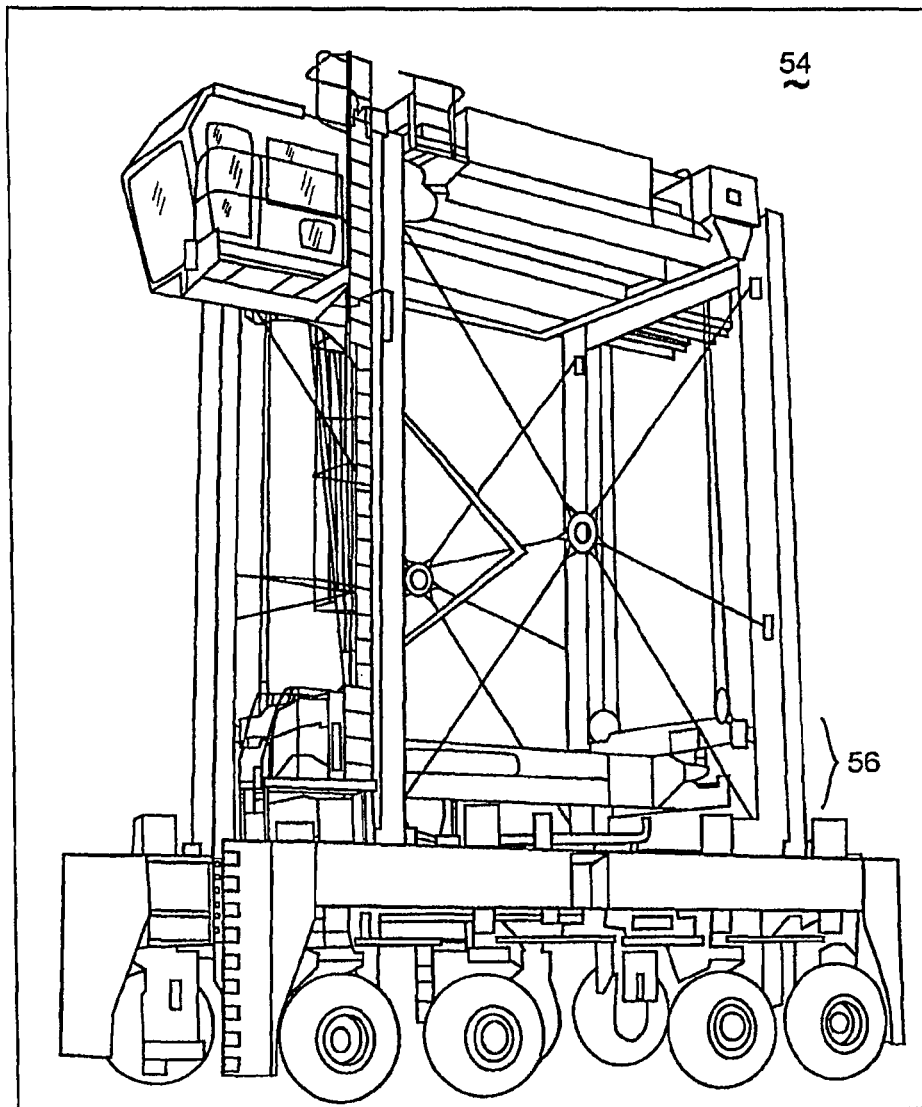


Fig. 4D



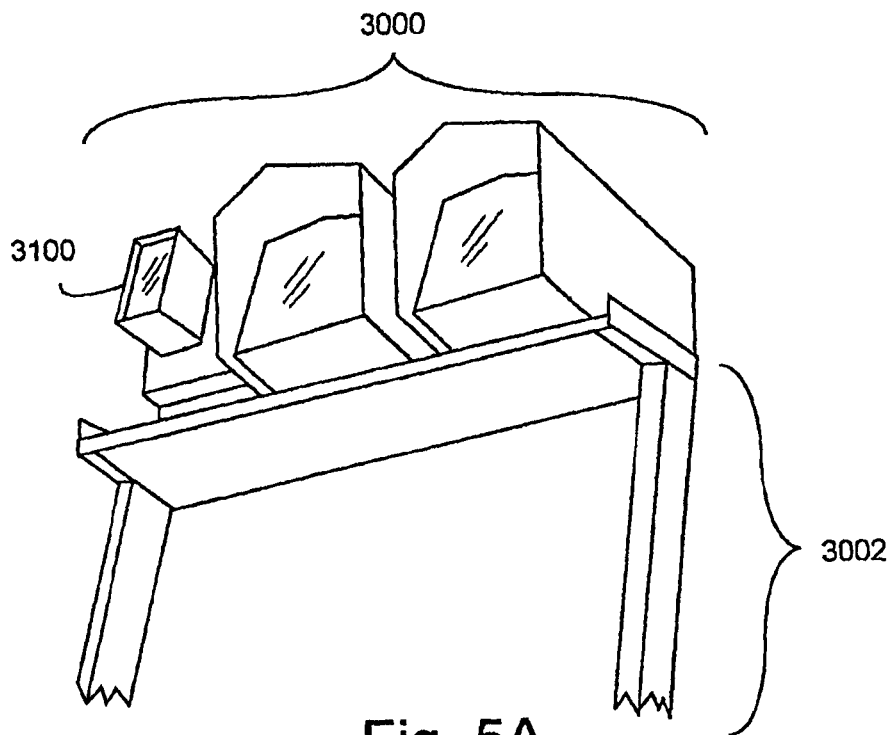


Fig. 5A

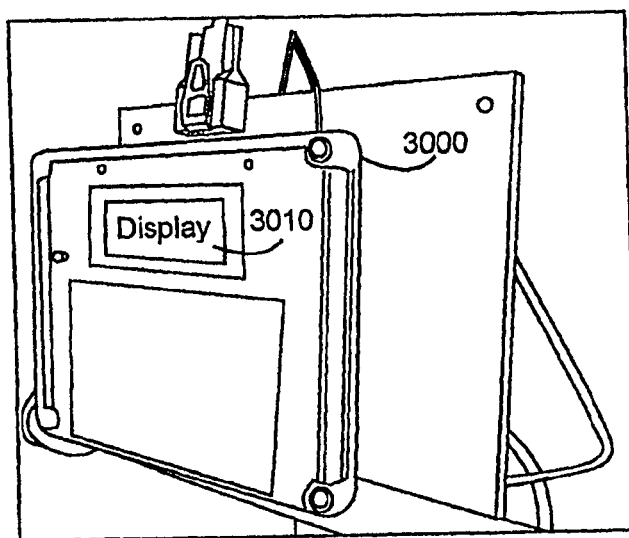


Fig. 5B

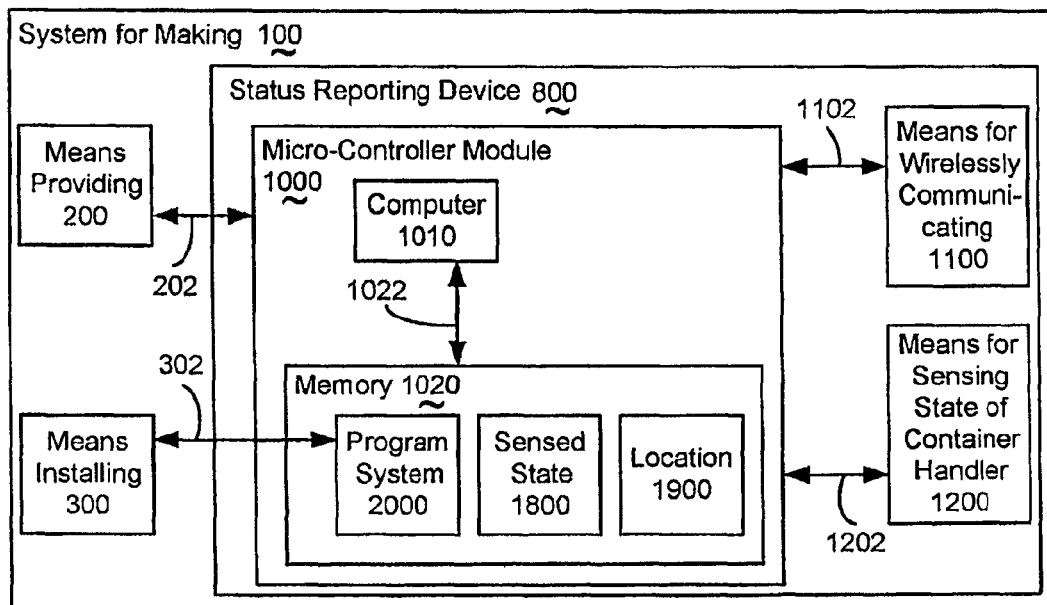


Fig. 6A

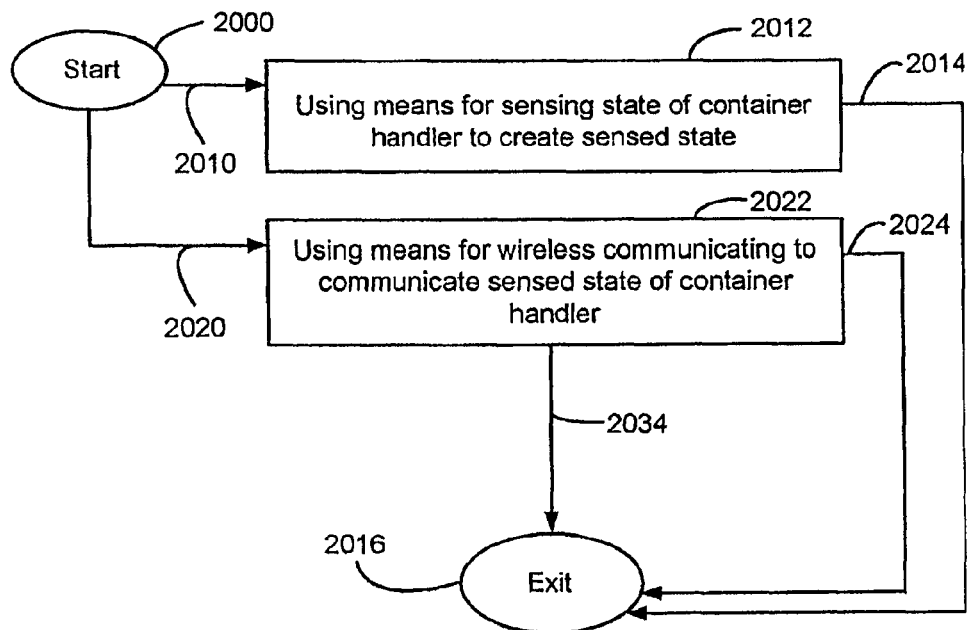


Fig. 6B

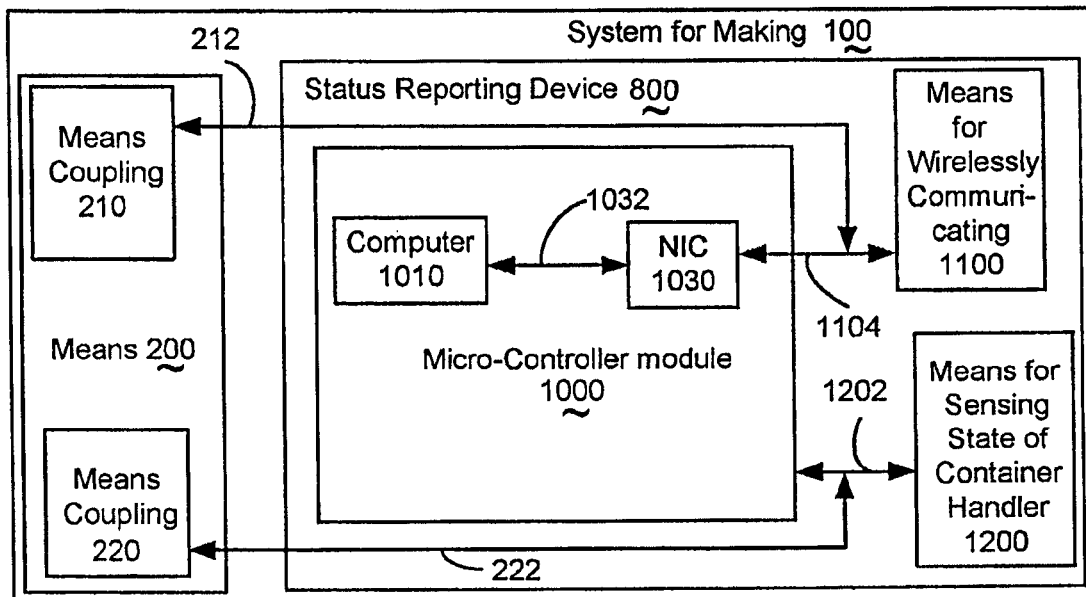


Fig. 7A

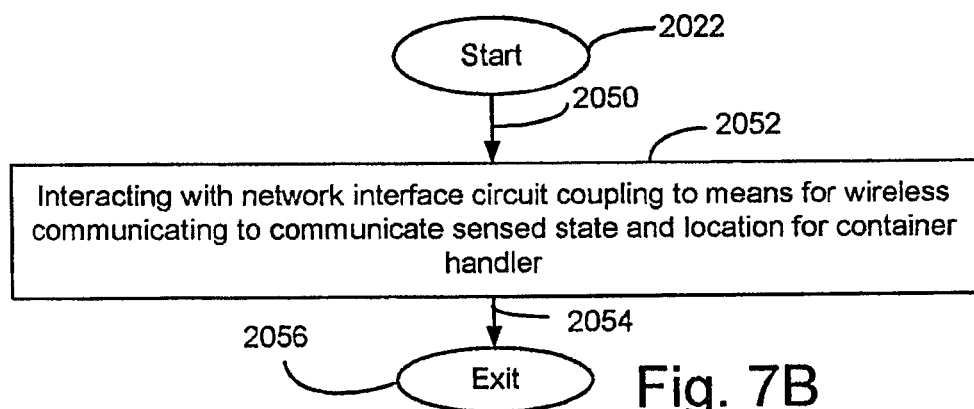


Fig. 7B

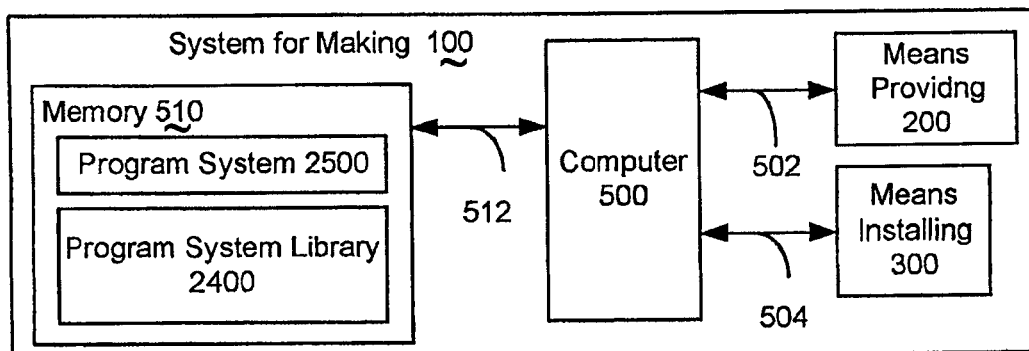


Fig. 7C

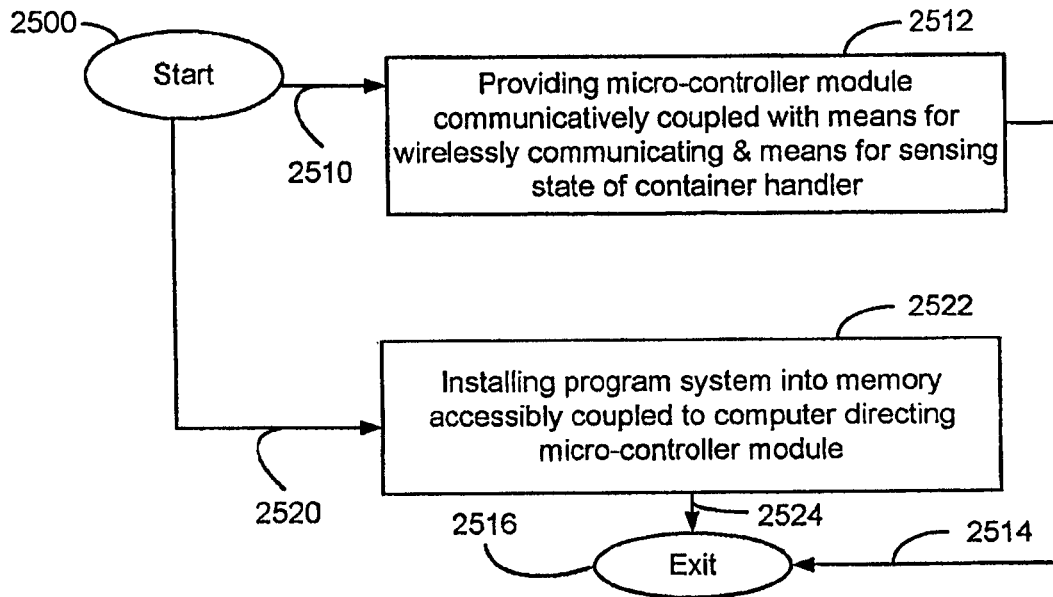


Fig. 8A

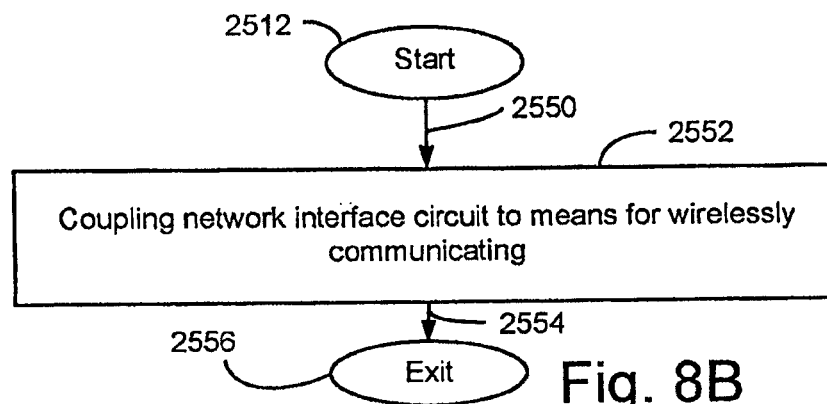


Fig. 8B

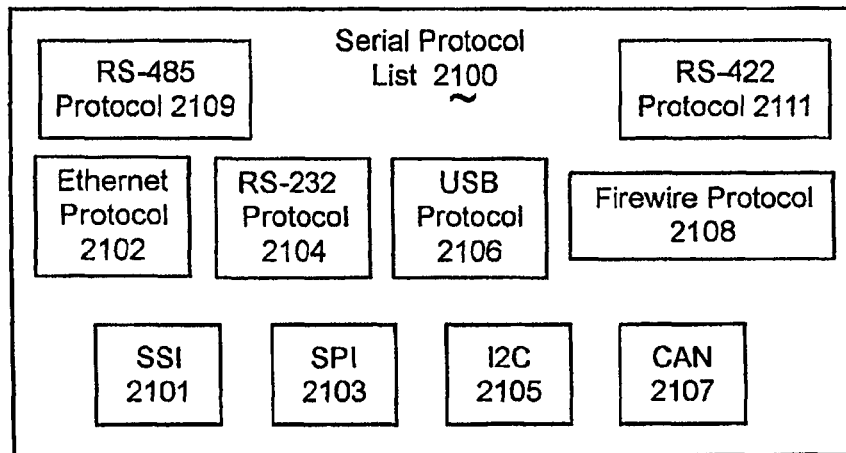


Fig. 8C

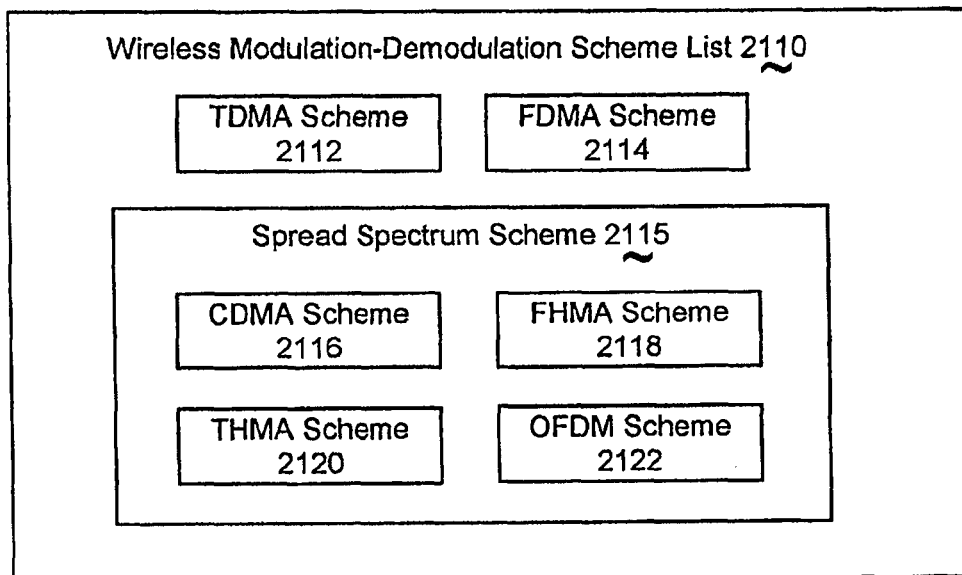


Fig. 8D

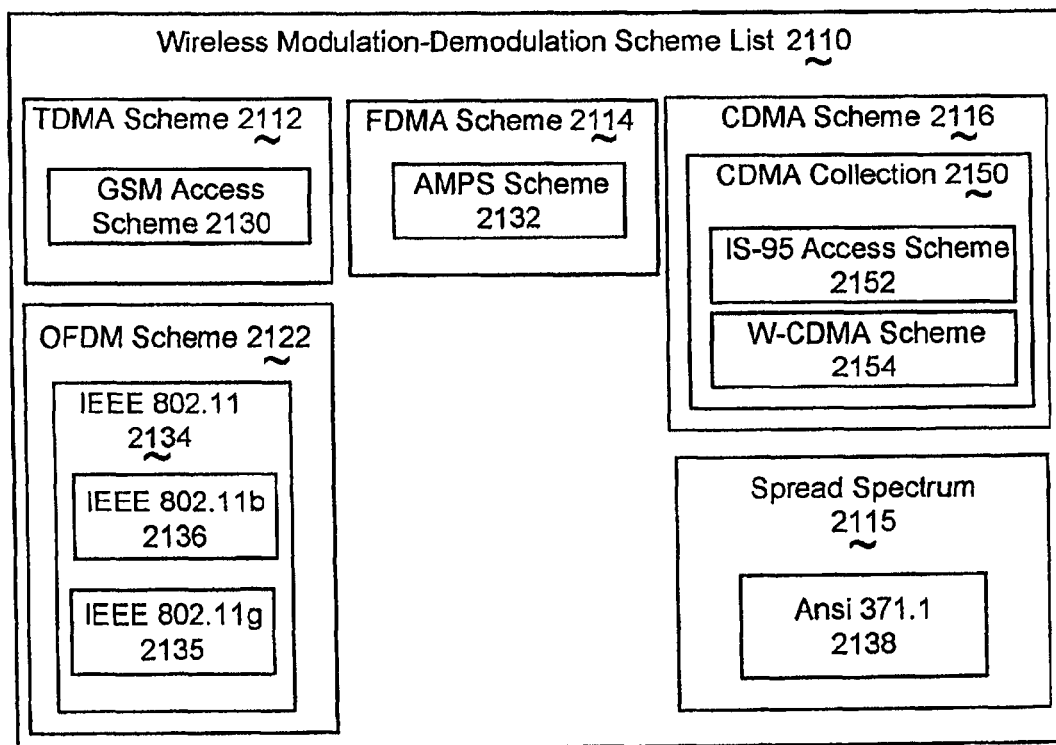


Fig. 9A

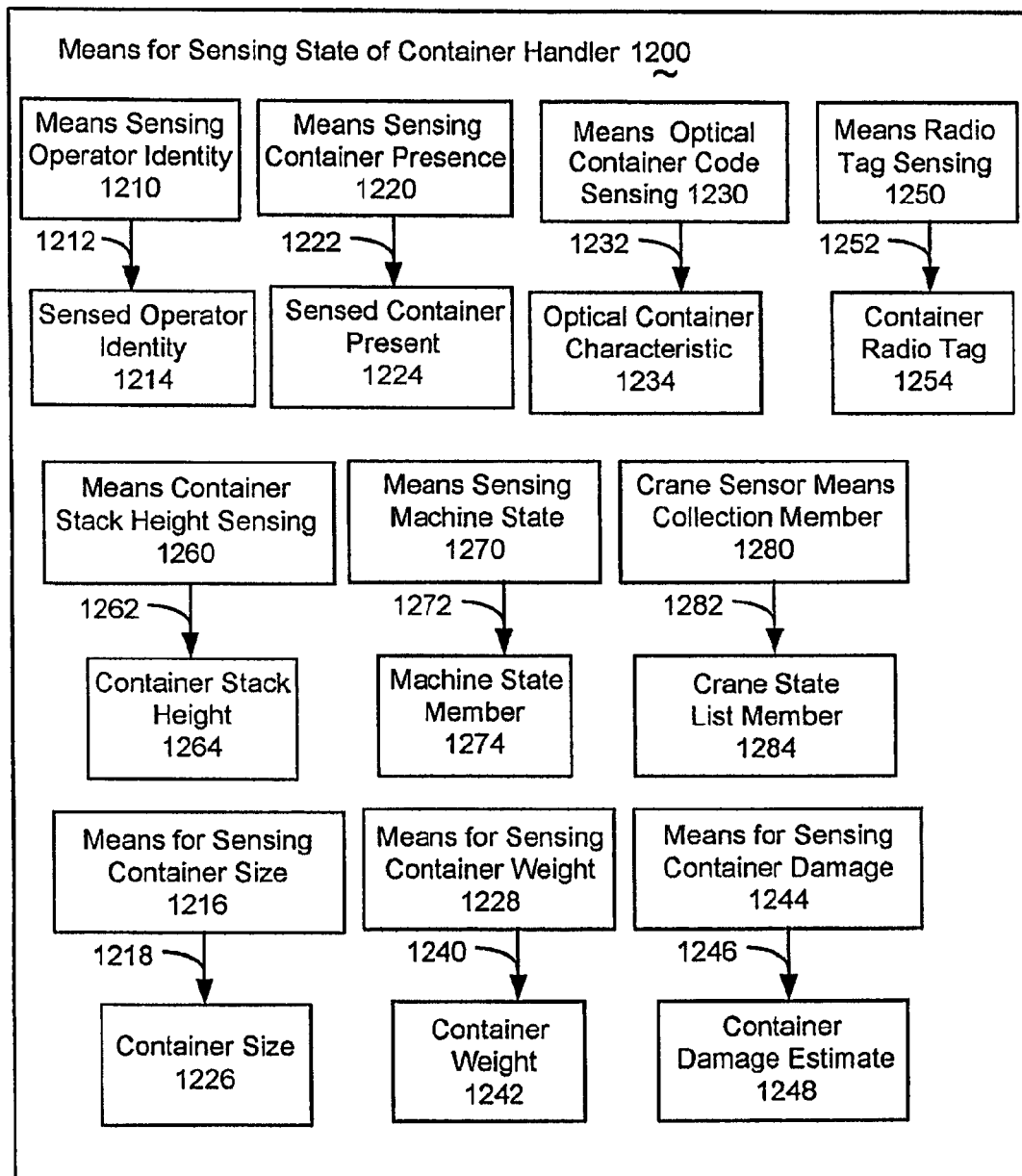


Fig. 9B

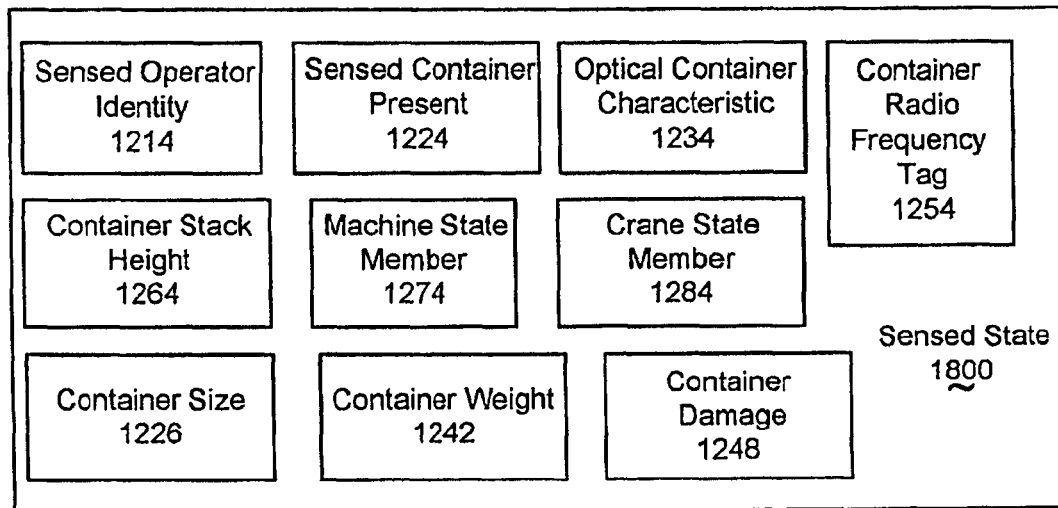


Fig. 10A

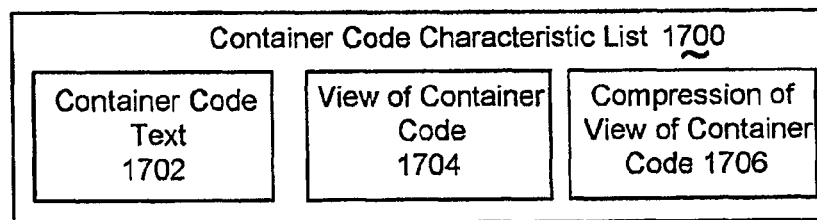


Fig. 10B

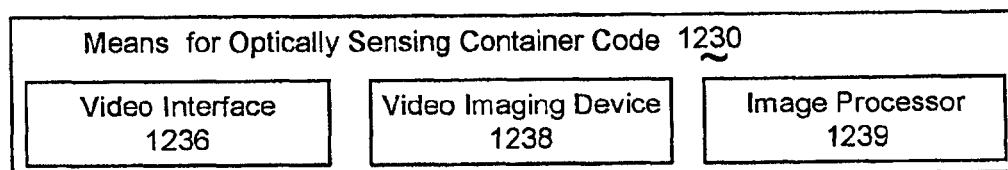


Fig. 10C



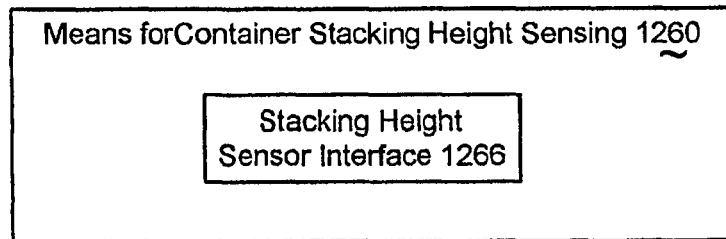


Fig. 10D

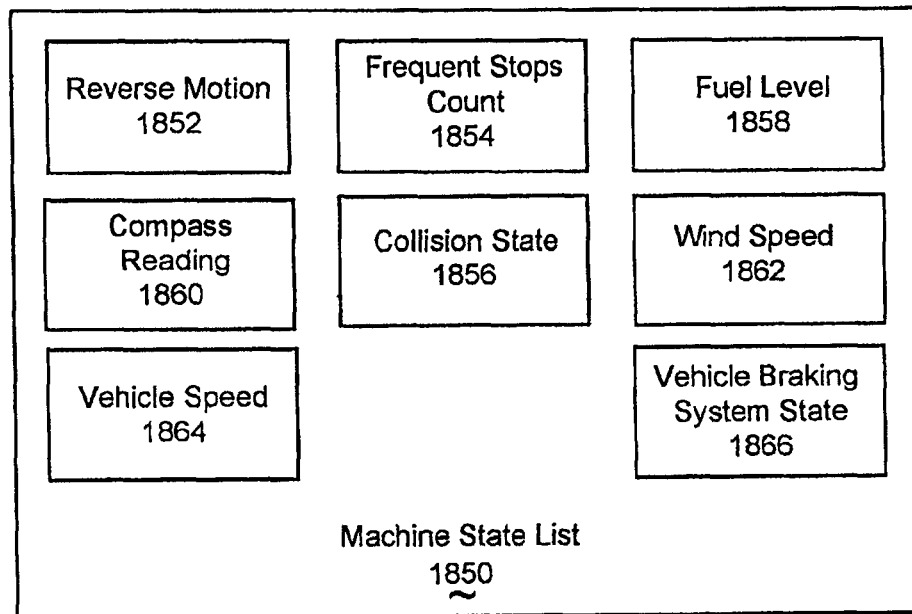


Fig. 10E

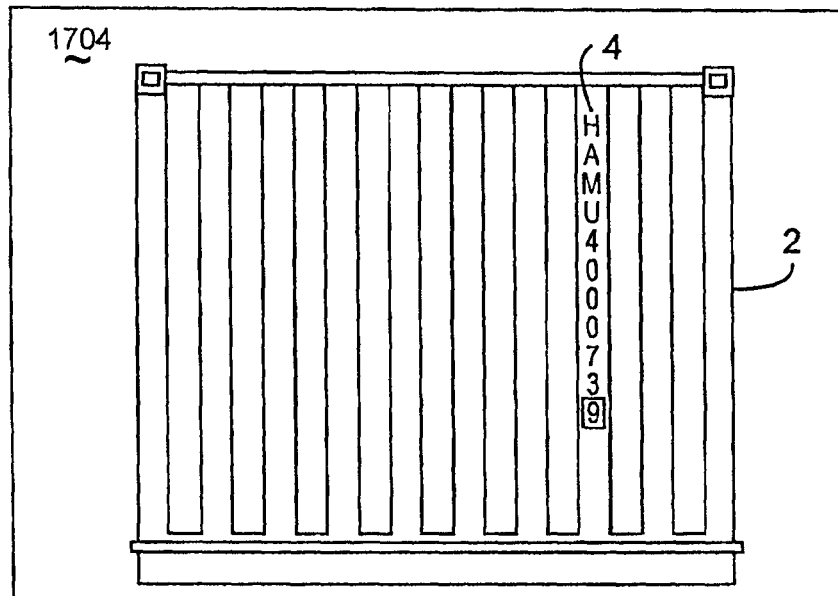


Fig. 11A

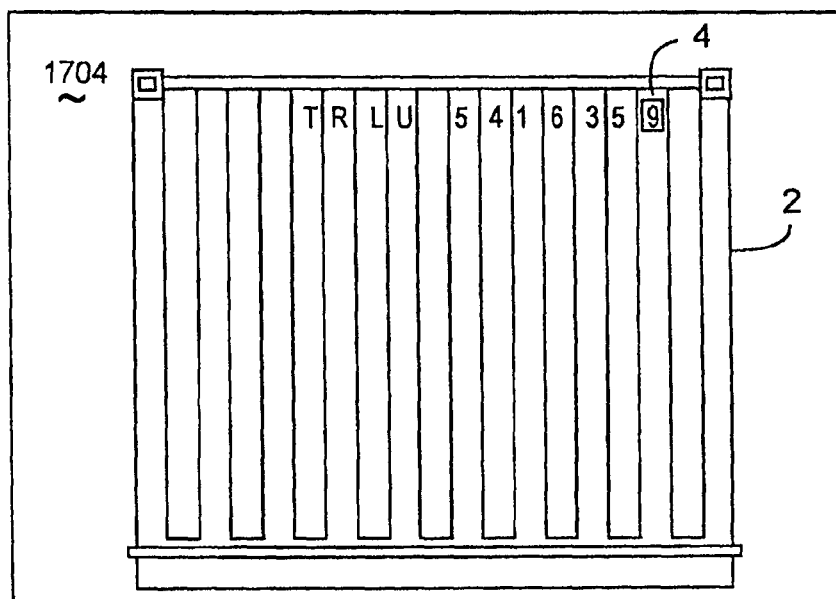


Fig. 11B

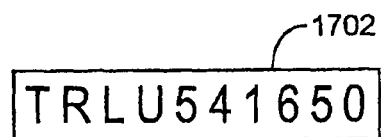


Fig. 11C

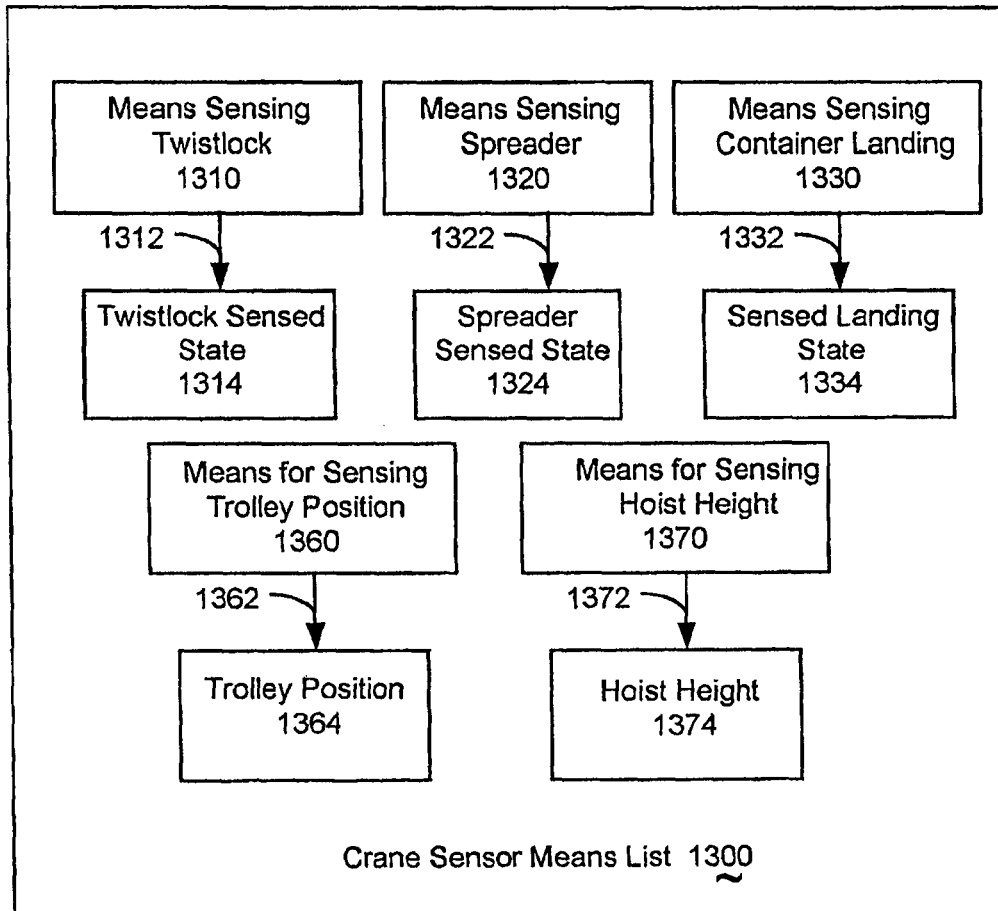


Fig. 12A

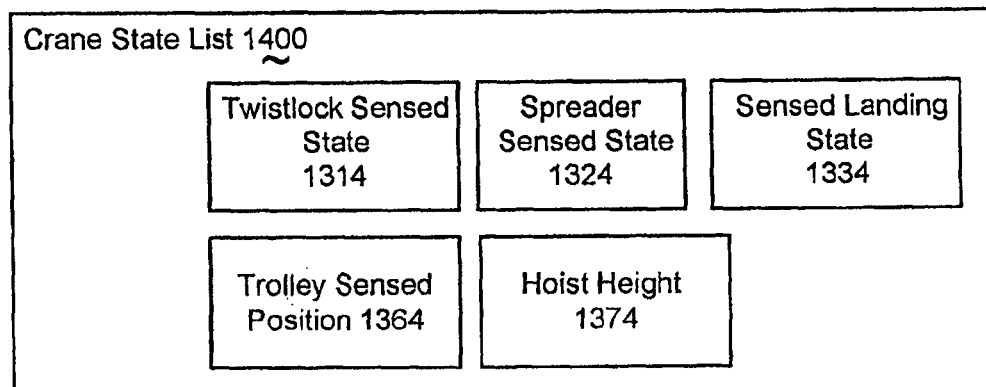


Fig. 12B

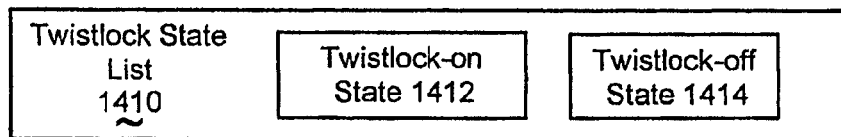


Fig. 12C

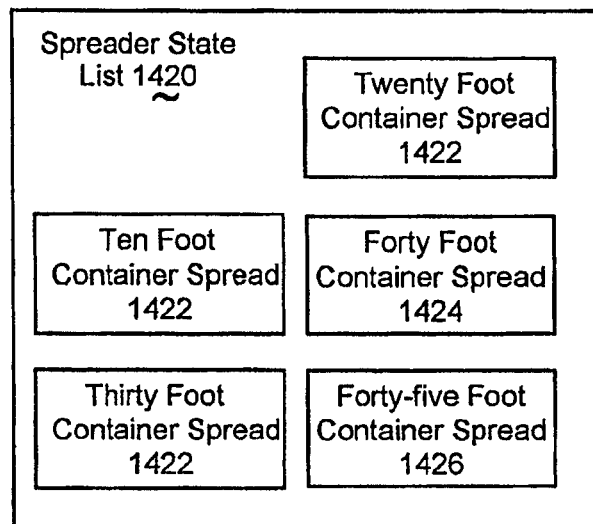


Fig. 12D

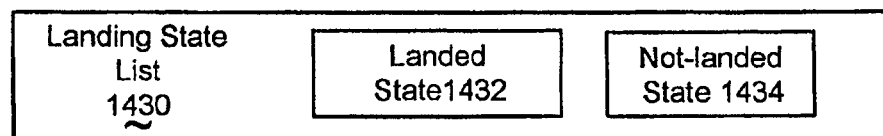


Fig. 12E

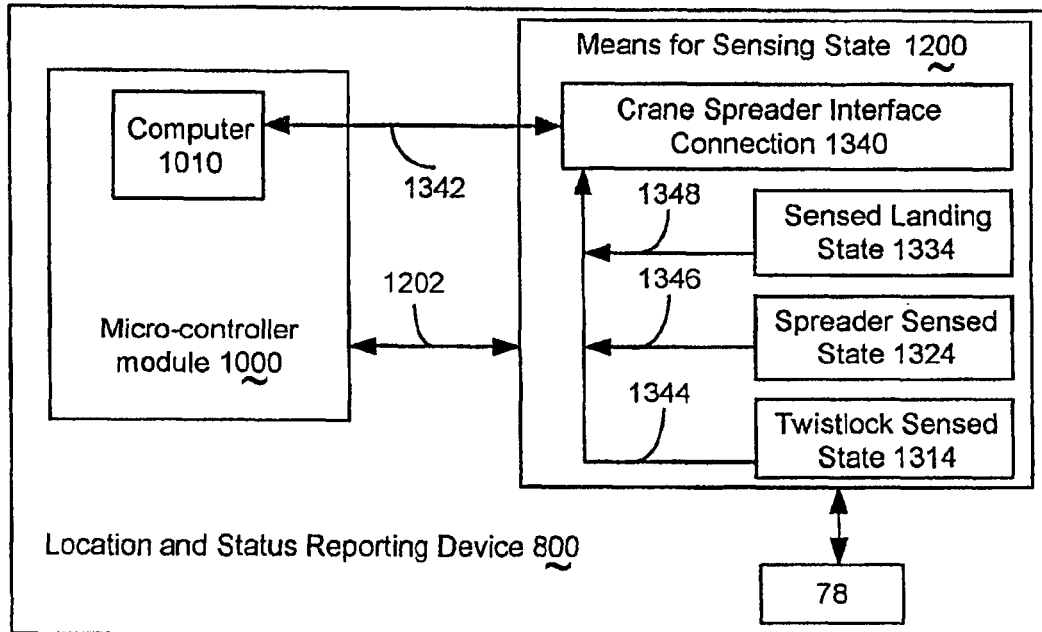


Fig. 13A

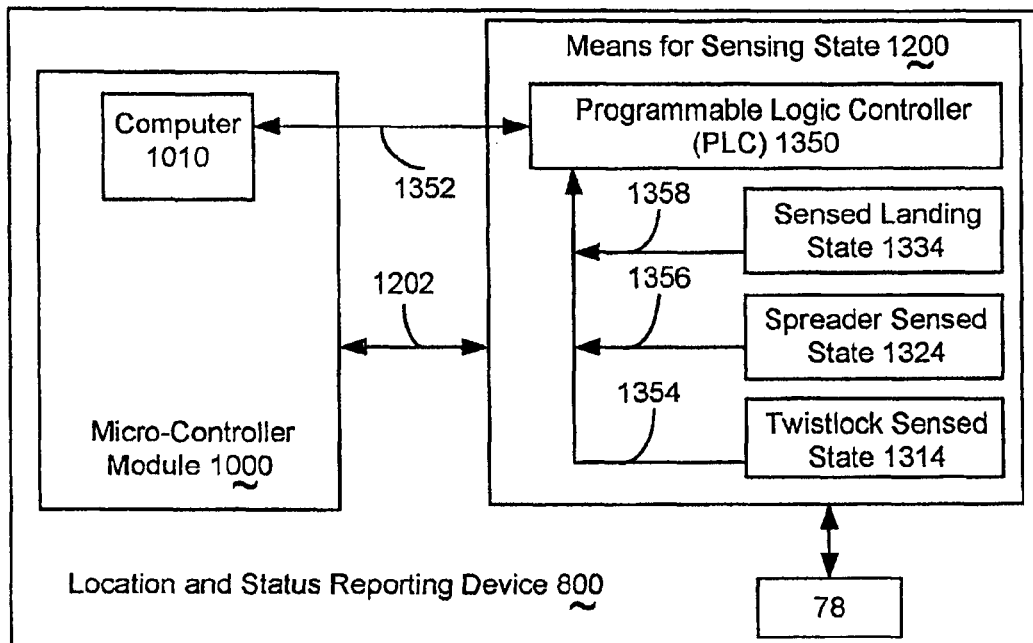


Fig. 13B

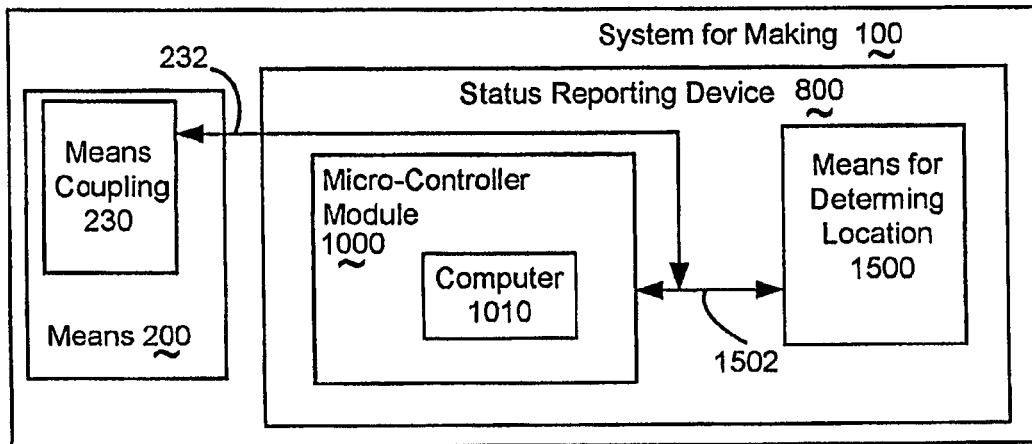
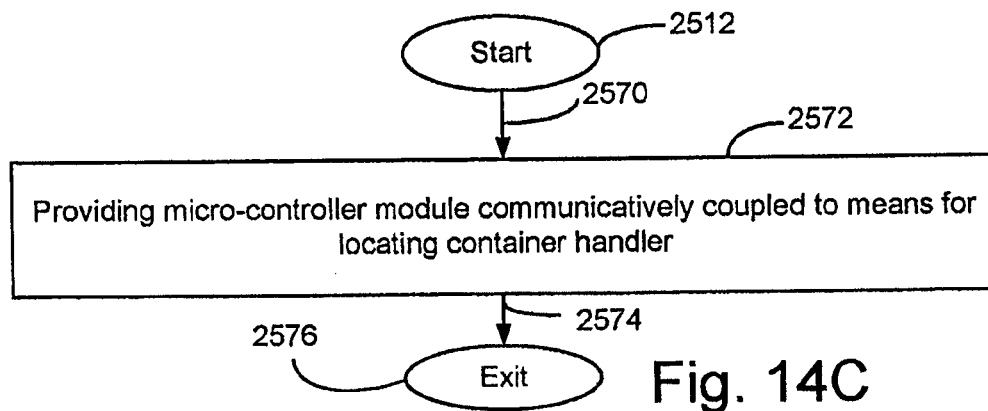
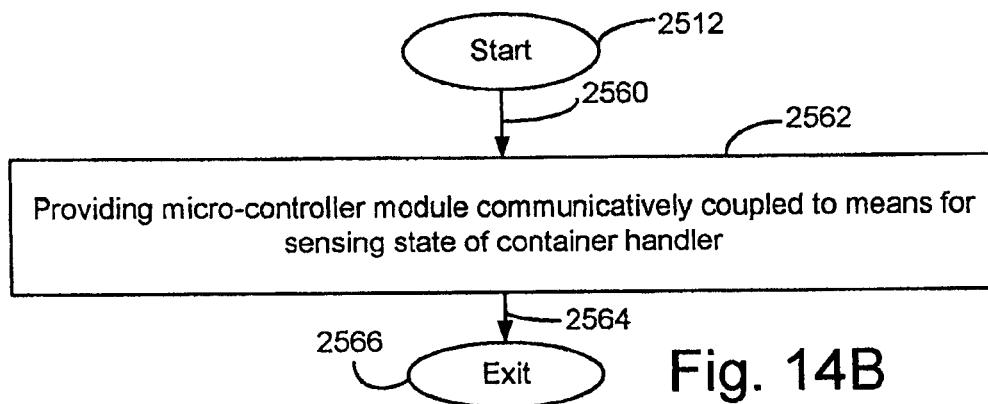


Fig. 14A



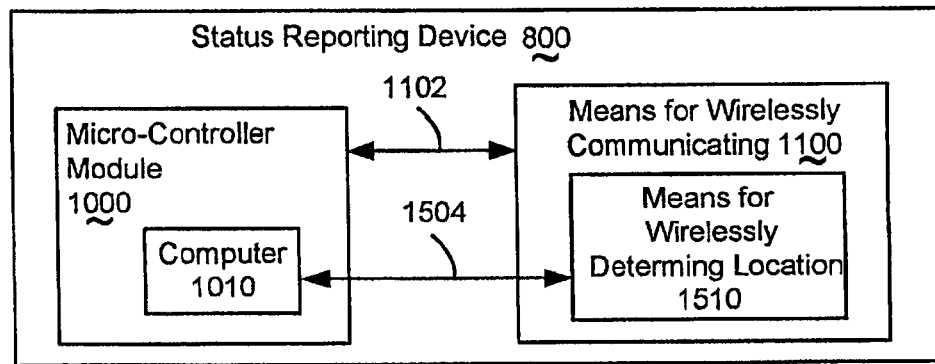


Fig. 15A

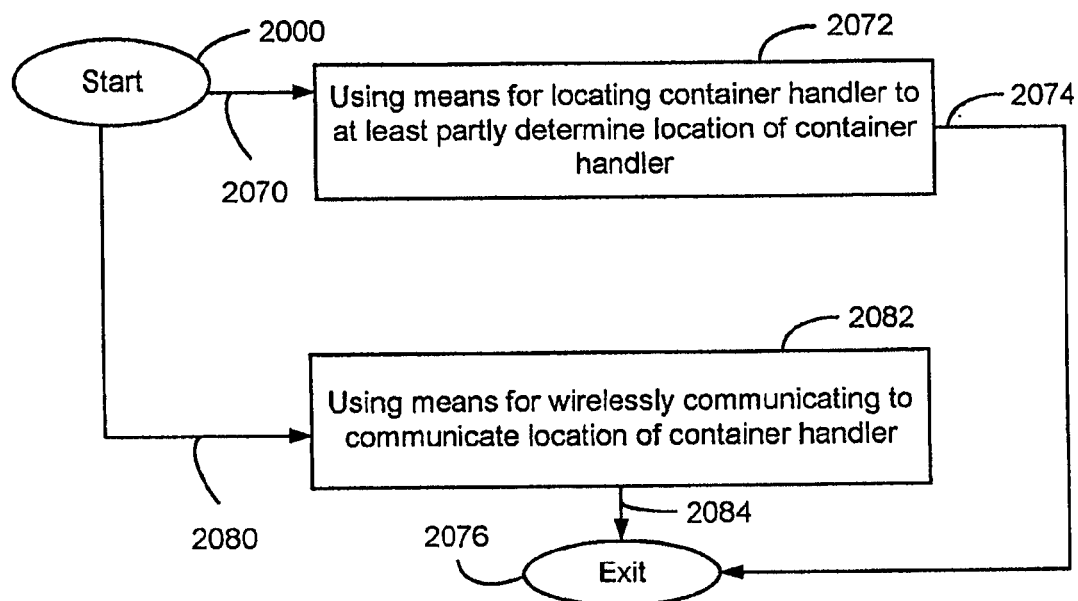


Fig. 15B

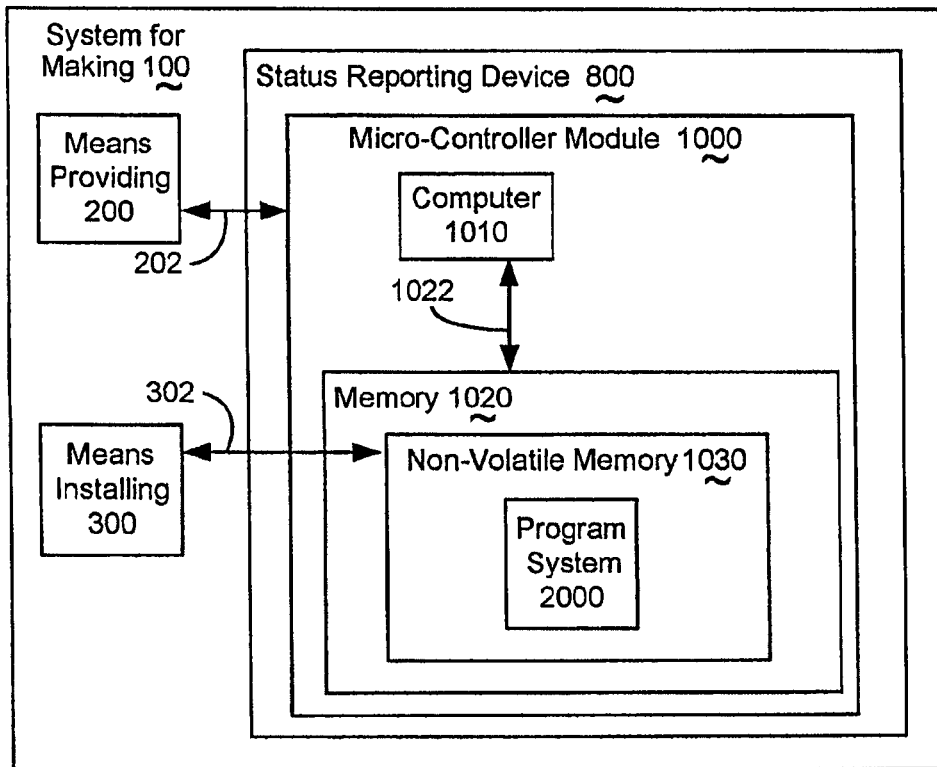


Fig. 16A

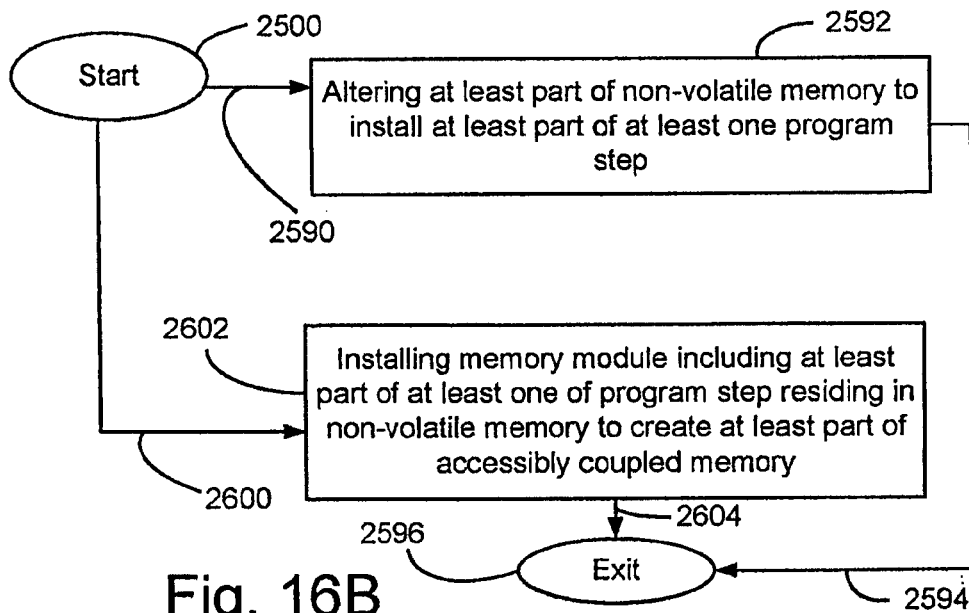
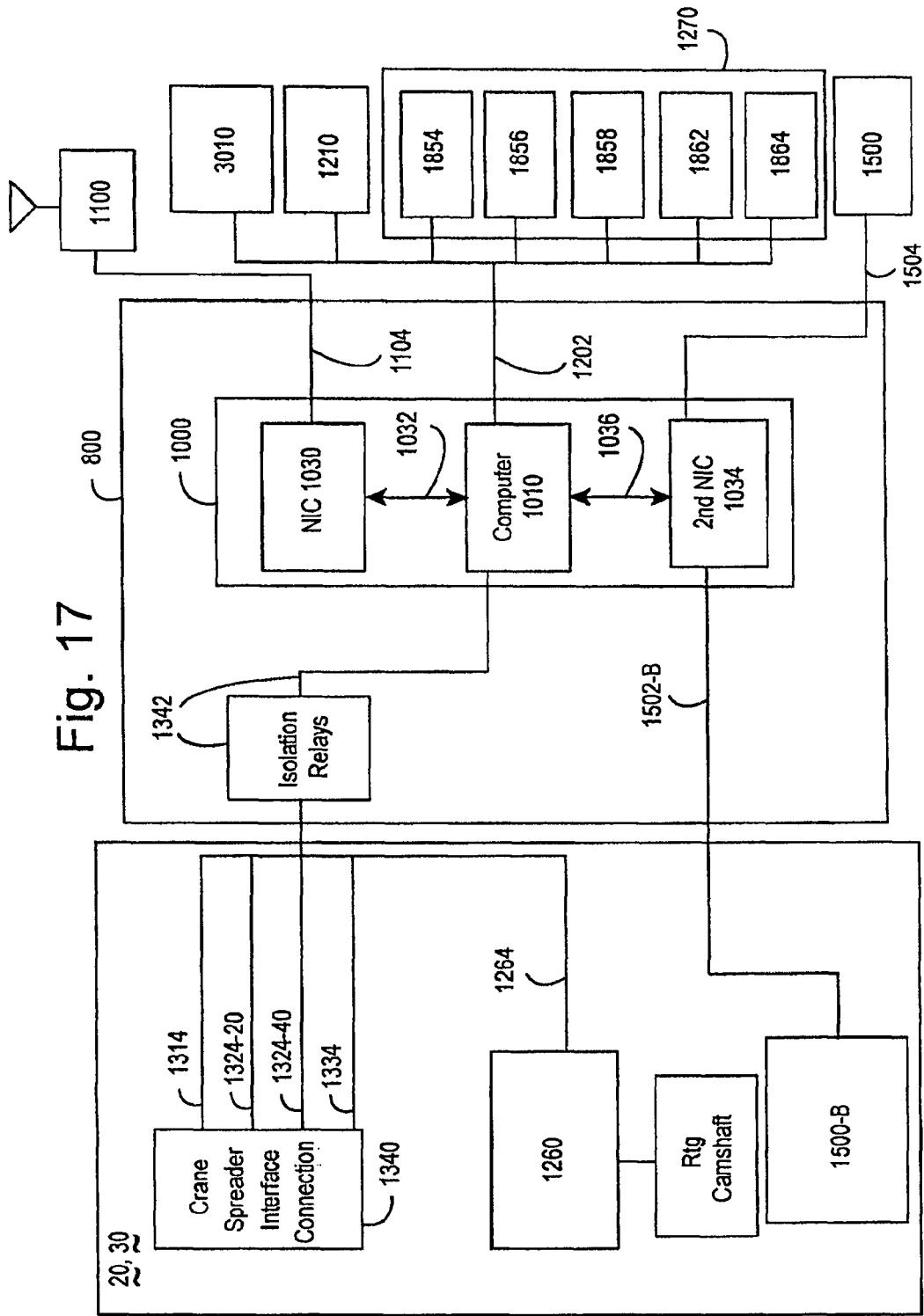


Fig. 16B





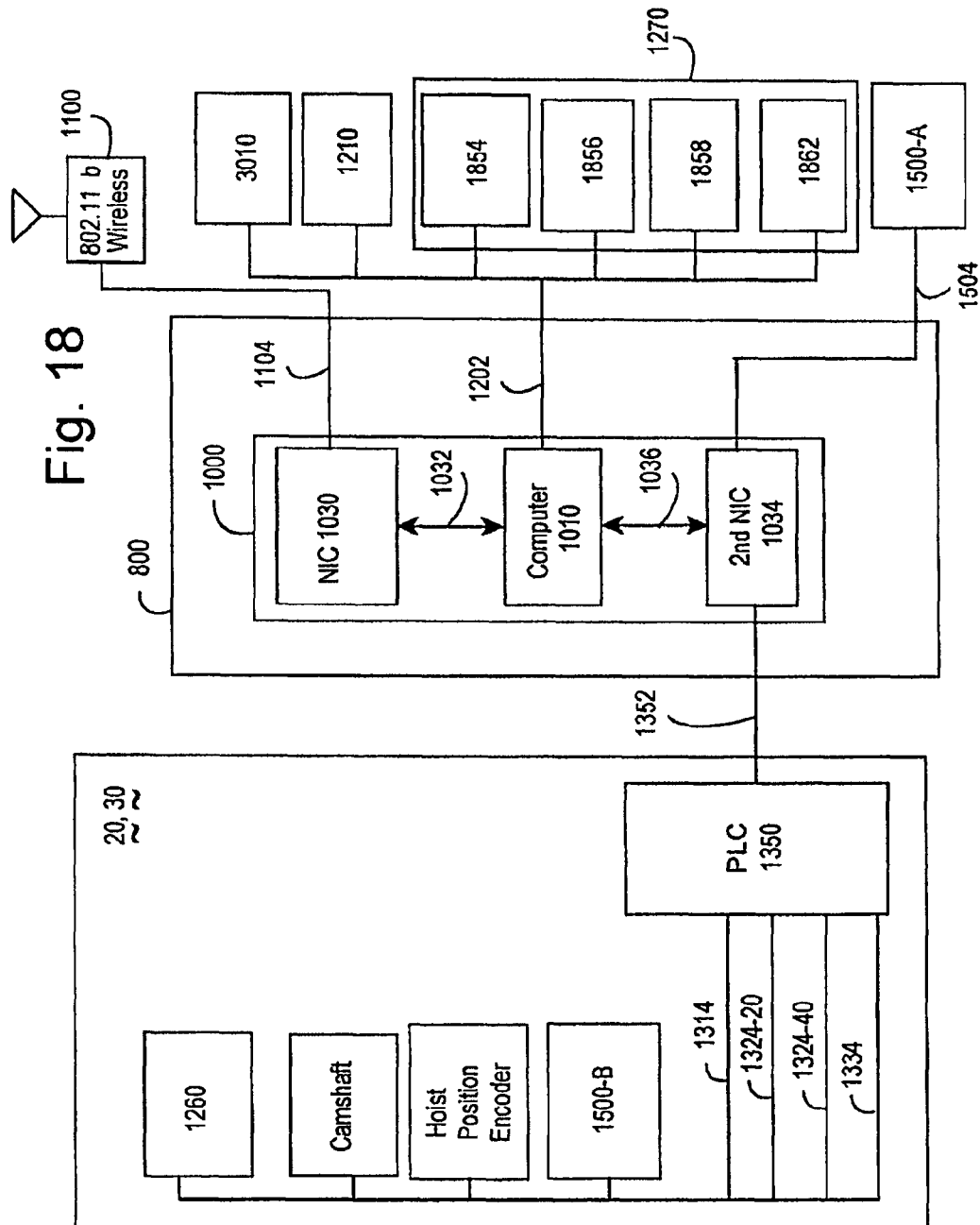
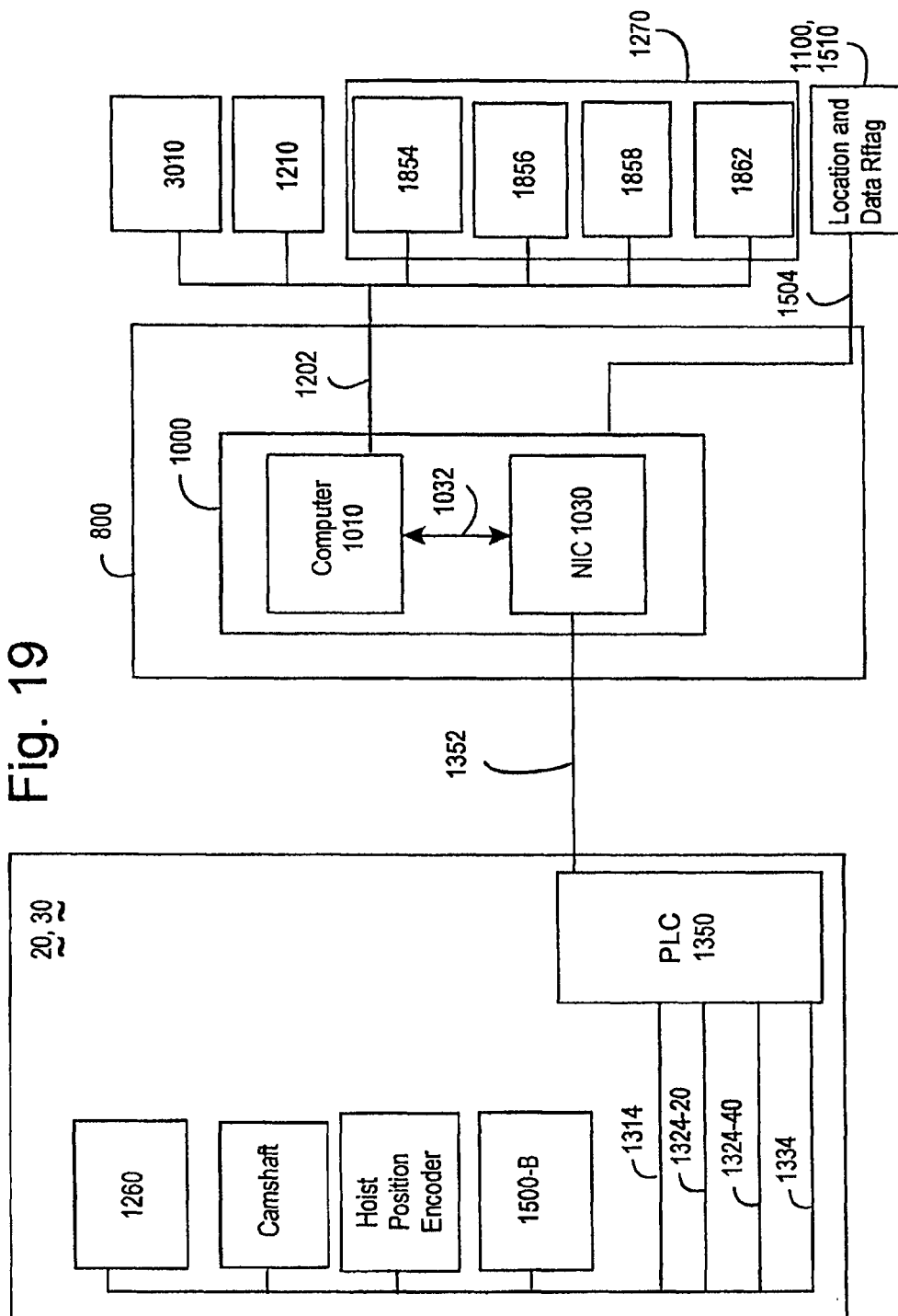
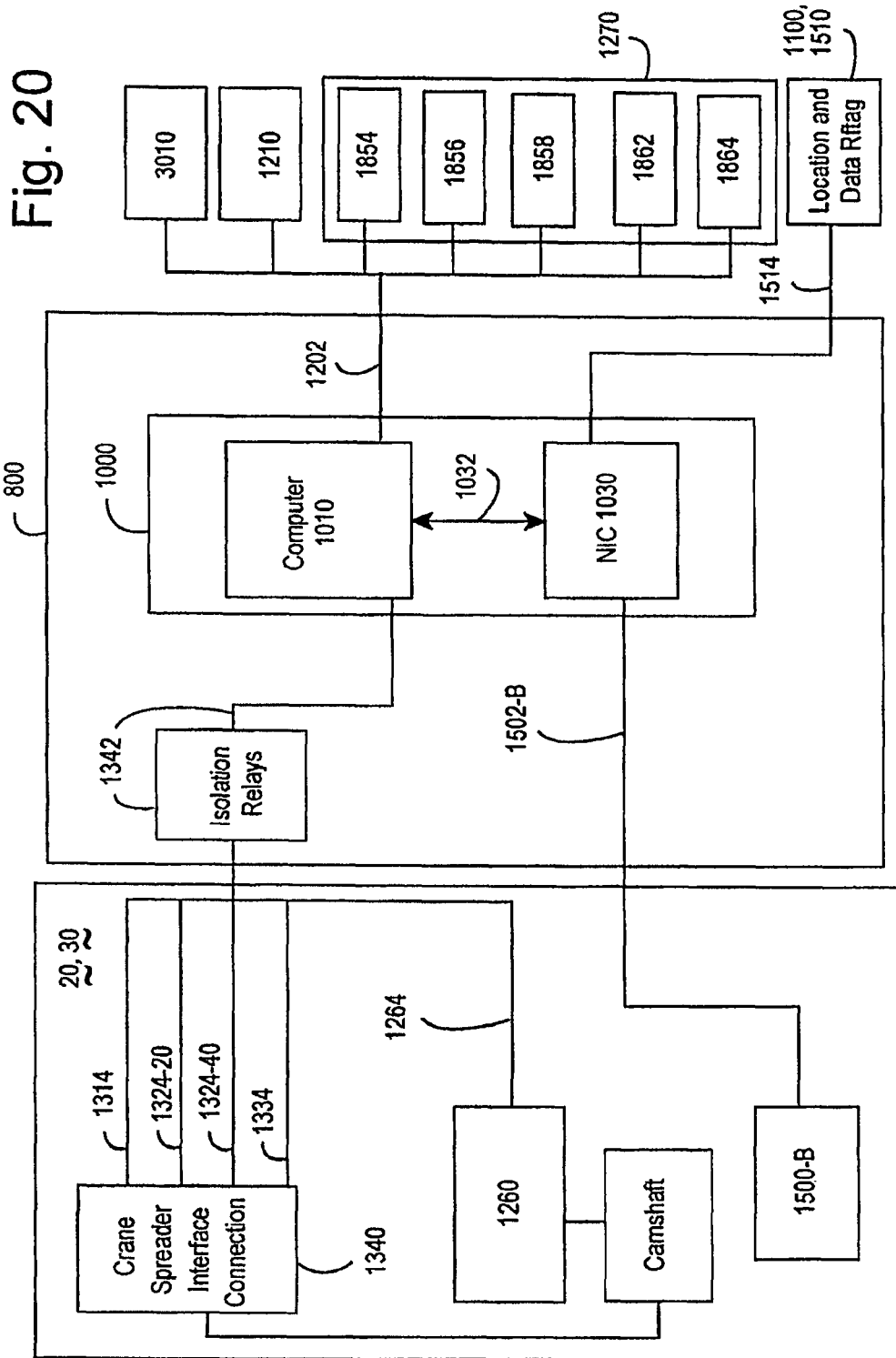
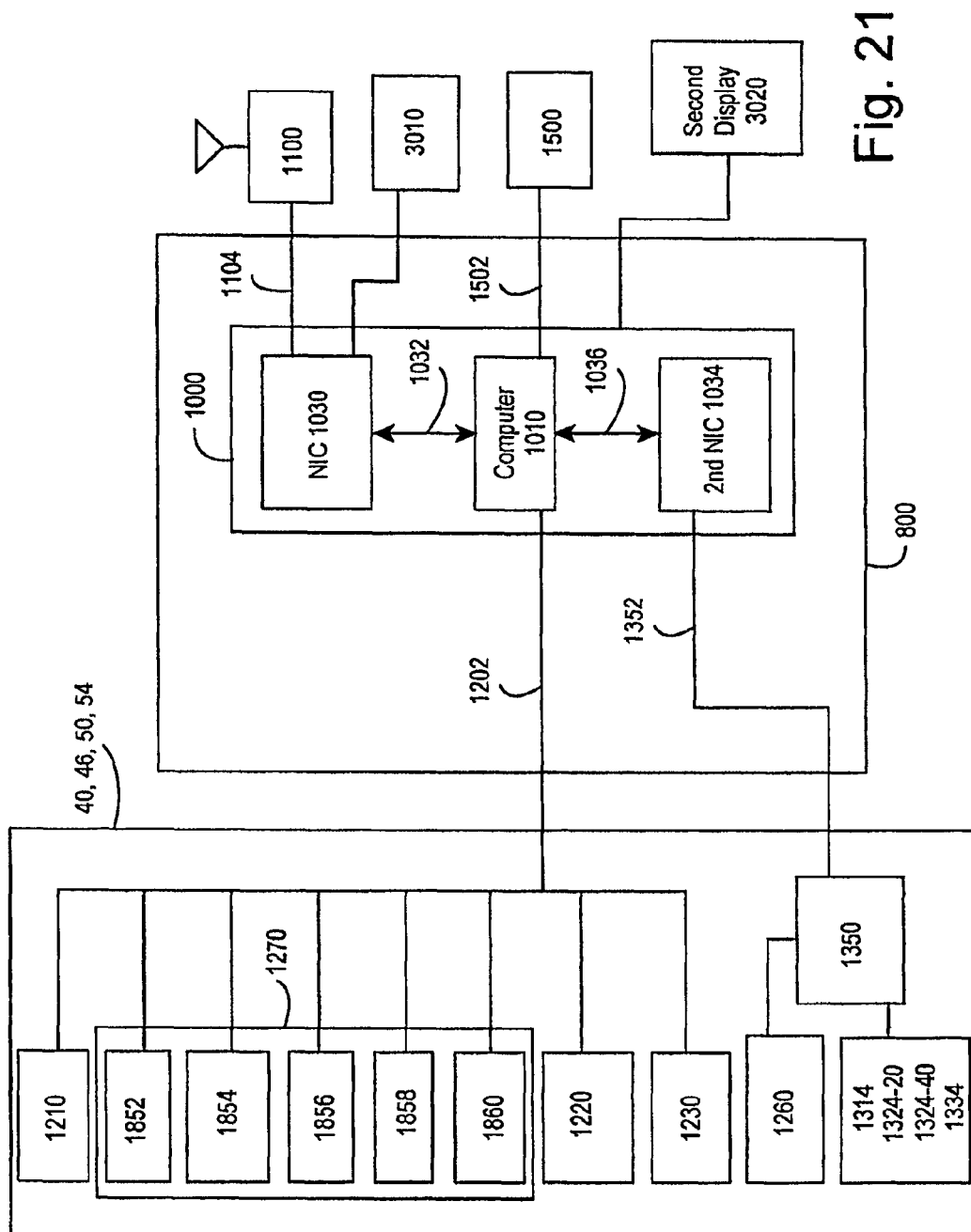


Fig. 19







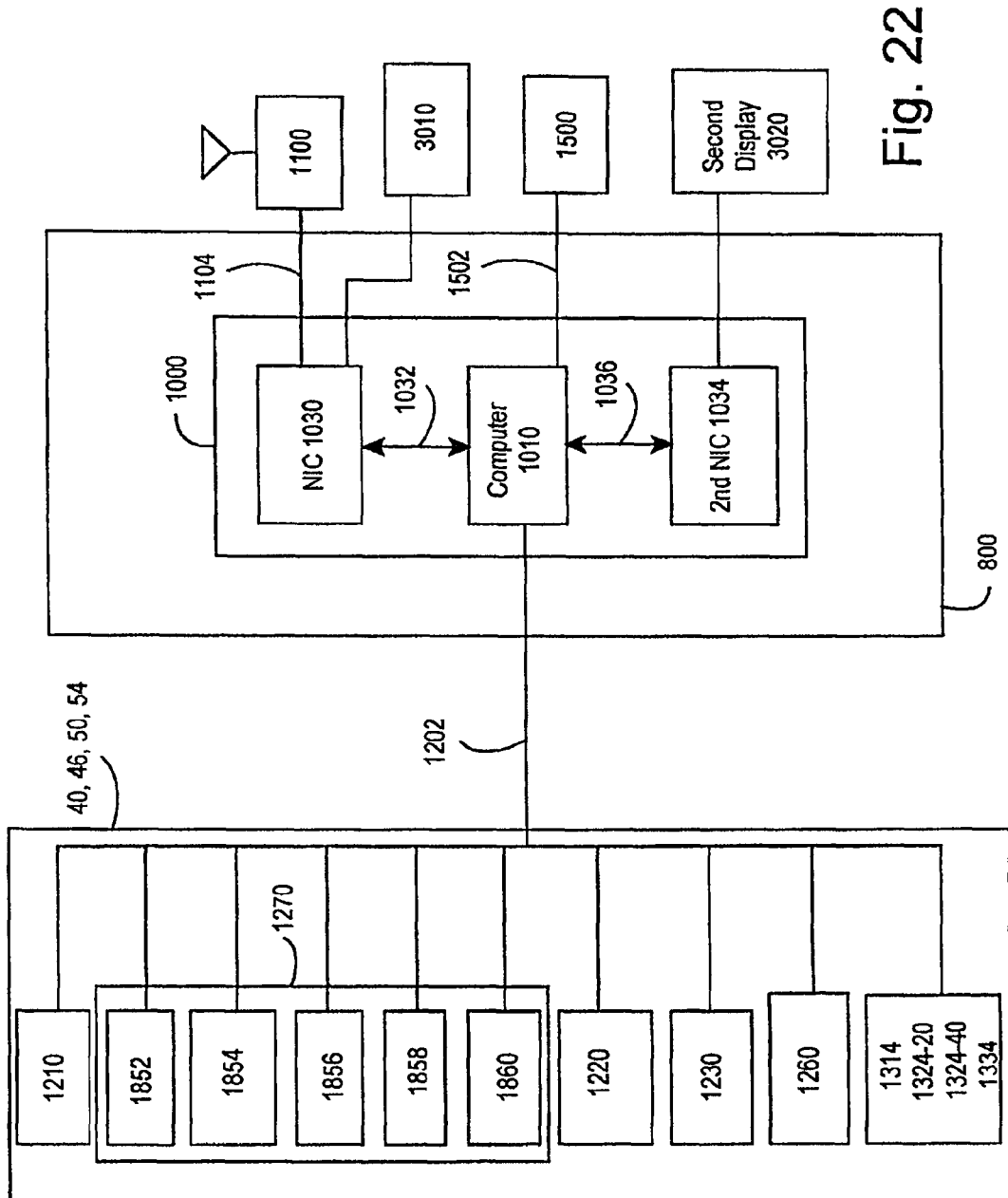


Fig. 22

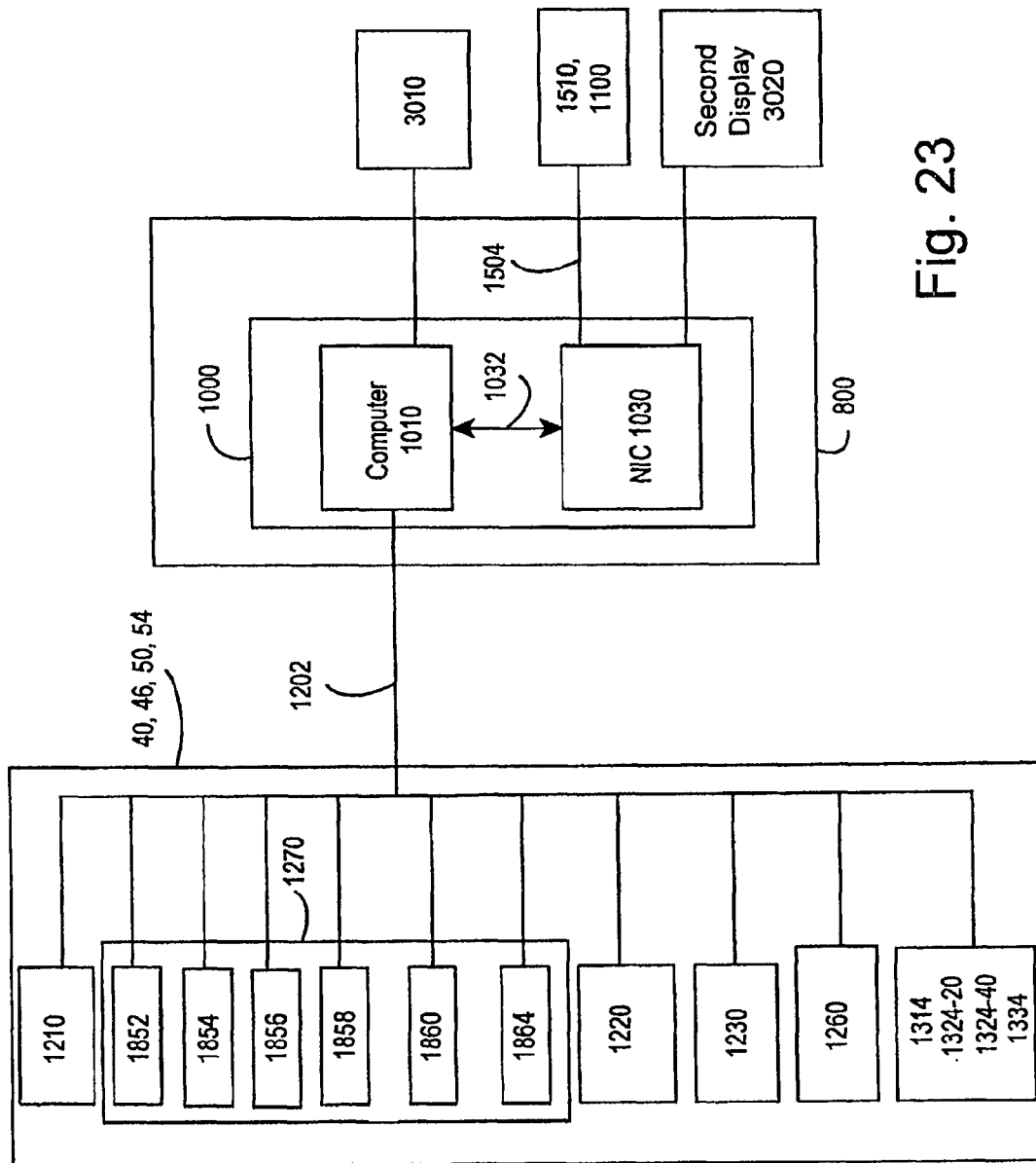


Fig. 23

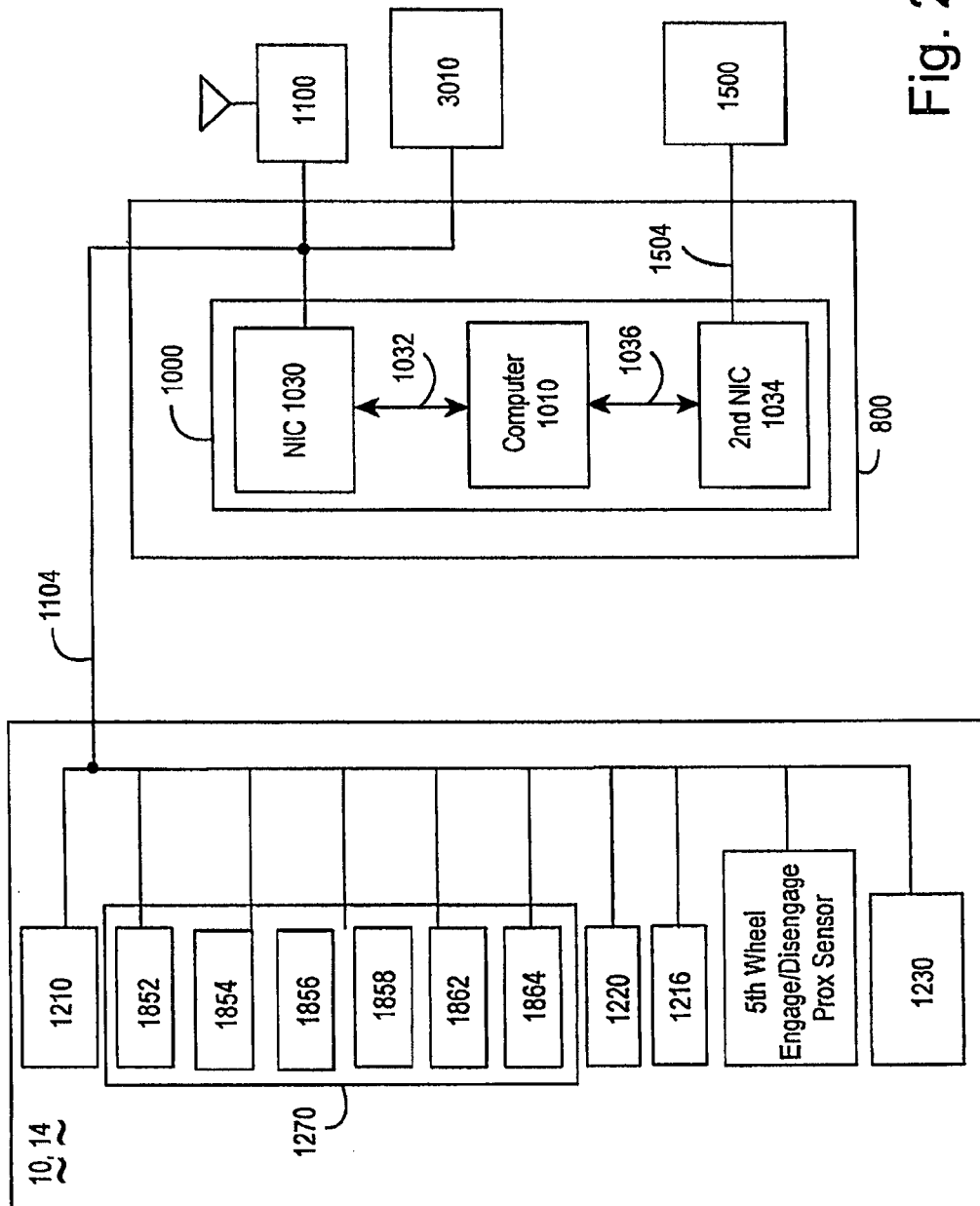


Fig. 24



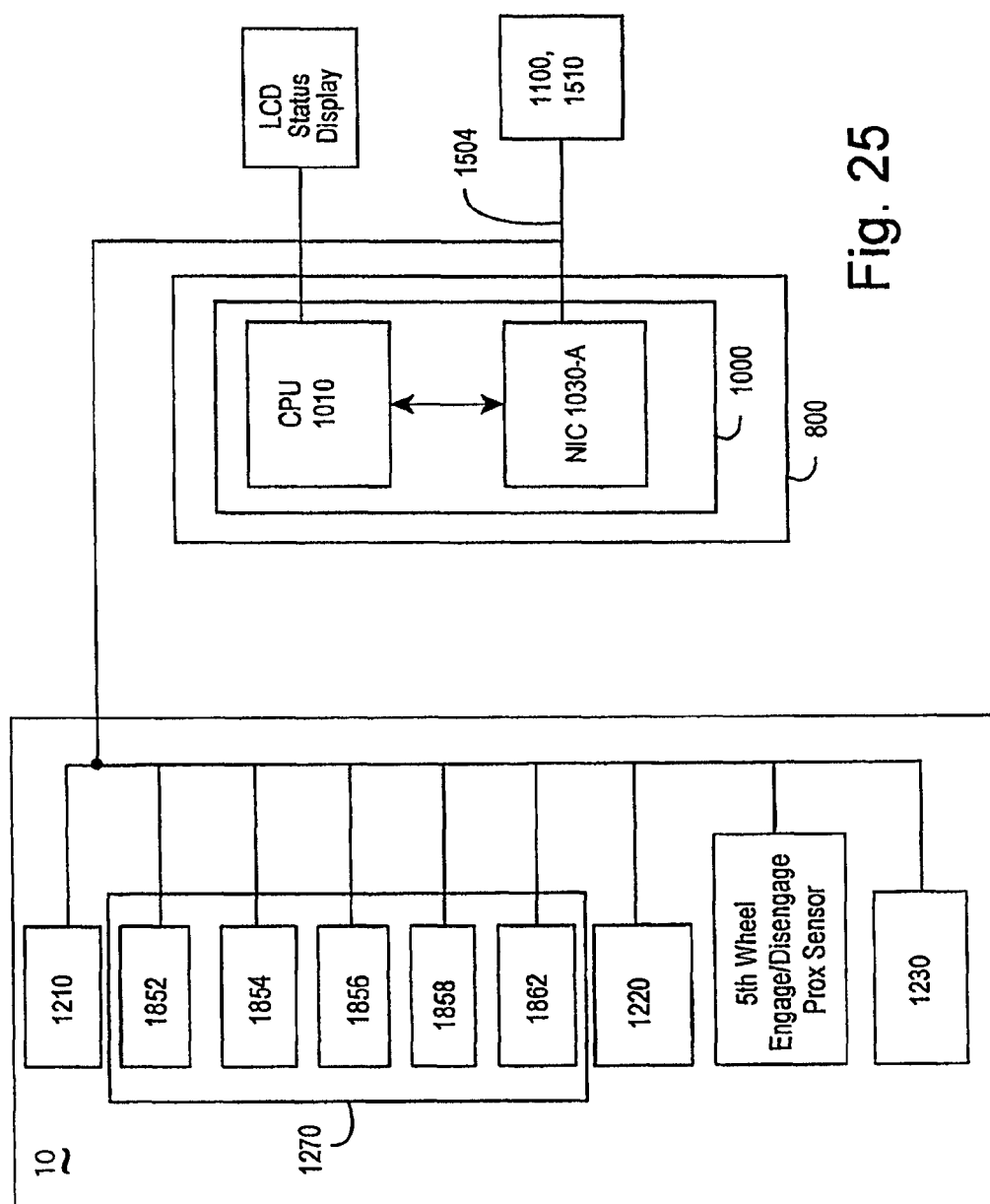


Fig. 25

# METHOD AND APPARATUS FOR MAKING STATUS REPORTING DEVICES FOR CONTAINER HANDLERS

## CROSS REFERENCES TO PRIORITY DOCUMENTS

This application is a continuation application of U.S. patent application Ser. No. 13/355,377 filed Jan. 20, 2012 (Now U.S. Pat. No. 8,525,671), which is a continuation application of U.S. patent application Ser. No. 12/574,624 filed on Oct. 6, 2009 (now U.S. Pat. No. 8,188,865), which is a continuation application of U.S. patent application Ser. No. 11/130,822, filed May 16, 2005, now U.S. Pat. No. 7,598,863, which further claims the benefit of the priority date of provisional patent application Ser. No. 60/571,009 filed May 14, 2004.

## BACKGROUND OF THE INVENTION

### 1. Field of the Invention

The present invention relates to status reporting devices for container handlers and methods of making these devices. A container handler will refer herein to a device, usually operated by a human operator, which moves a container of at least twenty feet in length.

### 2. Background Information

Container terminals are transfer points between marine and land-based shipping. These container terminals must maintain inventory control for an ever-increasing number of containers. The basic unit of transfer is a container, which comes in five sizes, a ten foot, a twenty foot, a thirty foot, a forty foot and a forty five foot size. These containers, when filled, may weigh up to 110,000 pounds, or 50,000 kilograms, making them impossible to move, except by machinery.

The last few years have seen increased demand for real-time reporting of container activity throughout the container terminals.

The point of transfer between marine transport and land-based transport is the quay side crane, or quay cranes, as they will be known hereafter. Berthing operations involve transferring containers between a container ship and a land transport by one of these quay cranes. There is often a need for mechanisms to inspect the containers and/or create long lasting records of the visual condition of the containers at the time of transfer. The clerks involved may intentionally or unintentionally mislead the container inventory management system and the terminal management. The container's contents may be damaged when it reaches its destination, leading to the possibility of lawsuits and insurance claims being brought against terminal management. Berthing operations may be seen as loading and unloading containers onto container ships.

The quay cranes deliver the containers onto UTR trucks, which sometimes carry the containers on specialized chassis known as bomb carts. The UTR trucks move containers around a terminal, transferring the containers between one or more stacking yards and the Quay cranes. In the stacking yards, a number of different cranes may be used to place the container in stacks, or possibly load them onto or unload them from trucks used for container movement outside the terminal.

There is an ever growing need to continuously monitor the status of the container handlers around a terminal. Overall terminal efficiency tends to be improved if the terminal management knows the status and/or location of each container handler and each container in the terminal. Illicit use of con-

tainer handlers may be minimized by use of operator identification devices. The container codes may be observed and recorded at various points in the terminal transfer operations. Photographs may be taken of the container conditions as it is leaving a ship, or being put on a ship.

There is however a problem of scale. While there are millions of containers entering and leaving a country such as the United States annually, there are nowhere near that many container handlers. Even worse, there are many different kinds of container handlers. Some, such as UTR trucks, Front End Loaders (FEL), and bomb carts handle containers differently from the cranes. As used herein, Front End Loaders will refer to Top Handlers (also known as Top Loaders) and Side Handlers (also known as Side Pickers). The crane based container handlers vary in structure greatly. Some have centralized controls, known as Programmable Logic Controllers (PLC), and some do not. As a consequence, these reporting devices, which enable container tracking, represent small production runs. These small production runs involve many variations in circuitry and couplings for these different types of container handlers, with the attendant high setup and manufacturing costs. A modular manufacturing method is needed for these reporting devices, which can readily account for the container handler variations, while minimizing cost and maximizing reliability.

In the last few years, a variety of radio frequency tagging devices have entered the marketplace. These devices can often provide a mechanism for identifying themselves, as well as reporting their location via a wireless communication protocol, often one or more variants IEEE 802.11. Some of these devices rely on a local wireless network to aid them in location determination. While these devices have uses, they do not satisfy all the needs that container handlers have for status reporting. What is needed are mechanisms and methods for using the capabilities of radio frequency tagging devices to provide an integrated solution to the needs of the various container handlers, to report on the container handler status, and/or provide observations of the container being handled.

## BRIEF SUMMARY OF THE INVENTION

The invention includes a mechanism and a method for making status reporting devices for container handlers. The devices are manufactured in a modular, highly efficient manner, which is able to use a relatively small number of different parts to serve the needs of a wide variety of container handlers.

A container handler will refer herein to a device, usually operated by a human operator, which can move a container of at least twenty feet in length. International commerce primarily uses containers of approximately ten feet, twenty feet, thirty feet, forty feet or forty-five feet in length.

The method making the status reporting devices includes the following steps. A micro-controller module is provided. A program system is installed into a memory, which a computer can access to direct the micro-controller module.

The micro-controller module is communicatively coupled with a means for wirelessly communicating and a means for sensing a state of the container handler.

The program system includes program steps residing in the memory. These program steps include the following. Using the means for sensing the state of the container handler to create a sensed state. And using the wirelessly communicating means to communicate the sensed state of the container handler.

In many preferred applications of the status reporting device, the means for wirelessly communicating is linked to a container inventory management system, sometimes also known as a terminal operating system. The sensed state may be preferably communicated to another computer, preferably associated with the terminal operating system.

The means for sensing may include, but is not limited to, means for any combination of the following.

Sensing an operator identity.

Sensing a container presence on, or coupled to, the container handler.

Optically sensing a container code on a container.

Radio frequency sensing a radio frequency tag on the container.

Sensing a stack height for the container.

Sensing at least one member of a machine state list of the container handler. The machine state list may include reverse motion, frequent stops count, collisions, fuel level, and compass readings. The machine state list may further include a wind speed and an equipment up-time.

Sensing at least one member of a crane state list. The crane state list may include a twistlock sensed state, a spreader sensed state, a sensed landing state, a trolley position, and a hoist height.

Sensing the container size.

Sensing the container weight.

Sensing container damage.

The means for wirelessly communicating may include a means for wirelessly determining the location of the container handler. Alternatively, the micro-controller module may be communicatively coupled to an at least partially separate means for locating the container handler. The means for locating may include an interface to a Global Positioning System (GPS). The means for wirelessly communicating may include a radio location-tag unit.

The container handler is at least one member of a container handler list comprising an UTR truck, a bomb cart, a rubber tire gantry crane, a quay crane, a side picker, a top loader, a top handler, a reach-stacker, a straddle carrier, and a chassis rotator.

The memory may include a non-volatile memory, which may further contain at least part of at least one of the program steps of the invention. Installing the program system may include altering at least part of the non-volatile memory, or installing a memory module containing at least part of at least one of the program steps in the non-volatile memory, creating at least part of the memory, which can be accessed by the computer. As used herein, the computer may be part of a micro-controller.

The invention includes apparatus for making the status reporting devices. The apparatus may include a second program system directing the implementation of the invention's method residing in memory accessibly coupled to a second computer. The second computer may control an assembly device receiving the micro-controller module, the means for wirelessly communicating, and the means for sensing the state of the container handler to create the reporting device.

#### BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 shows three container handlers: a rubber tire gantry (RTG) crane and a UTR truck hauling a bomb cart;

FIG. 2 shows another container handler referred to herein as a quay side crane;

FIG. 3A shows another container handler referred to herein as a side picker;

FIG. 3B shows a stack of containers defining what is referred to herein as a stacking height;

FIG. 4A shows another container handler referred to herein as a reach stacker;

FIG. 4B shows the container handler list;

FIG. 4C shows a top handler;

FIG. 4D shows a straddle carrier;

FIGS. 5A and 5B show housing of the status reporting device and sensors for use on various container handlers;

FIG. 6A shows a system for making a status reporting device for the container handlers of FIGS. 1, 2, 3A, 4A, and 4B;

FIG. 6B shows a flowchart of the program system in the status reporting device of FIG. 6A;

FIG. 7A shows a refinement of the status reporting system of FIG. 6A coupled by a Network Interface Circuit (NIC) to the means for wirelessly communicating;

FIG. 7B shows a detail flowchart of FIG. 6B further using the means for wirelessly communicating;

FIG. 7C shows a further, often preferred embodiment of the manufacturing system of FIGS. 6A and 7A, including a second computer at least partly directing the means for creating the status reporting device;

FIG. 8A shows a flowchart of the program system of FIG. 7C, embodying certain aspects of making the status reporting device of FIGS. 6A and 7A;

FIG. 8B shows a detail of FIG. 8A further providing the micro-controller module to the system of FIG. 6A;

FIG. 8C shows a serial protocol list;

FIG. 8D shows a wireless modulation-demodulation scheme list;

FIG. 9A shows a refinement of part of the wireless modulation-demodulation scheme list of FIG. 8D;

FIG. 9B shows some refinements of the means of FIGS. 6A and 7A for sensing the state of the container handler;

FIG. 10A shows some refinements of the sensed state of FIGS. 6A and 7A;

FIG. 10B shows a container code characteristic list;

FIG. 10C shows some preferred alternative embodiments of the means for optically sensing the container code on the container of FIG. 9B;

FIG. 10D shows a further preferred embodiment of the means for sensing the stacking height, including a stacking height sensor interface to a stacking height sensor on the container handler;

FIG. 10E shows a preferred embodiment of the machine state list;

FIGS. 11A and 11B show example views of FIG. 10B, of the container code optically viewed on the side of container of FIGS. 1, 3A, and 4A;

FIG. 11C shows an example of the container code text of FIG. 10B;

FIG. 12A shows some details of the crane sensor means list related to members of FIG. 9B;

FIG. 12B shows some details of the crane state list related to members of FIGS. 9B and 10A;

FIG. 12C shows some details of a twistlock state list related to members of FIG. 12A;

FIG. 12D shows some details of the spreader state list related to members of FIG. 12A;

FIG. 12E shows some details of the landing state list related to members of FIG. 12A;

FIG. 13A shows a refinement of the status reporting device 800 of FIGS. 6A and 7A where the sensing means includes coupling to a crane spreader interface connection;

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FIG. 13B shows a refinement of the status reporting device of FIGS. 6A and 7A where the sensing means includes coupling to a Programmable Logic Controller (PLC);

FIG. 14A shows the providing means of FIGS. 6A and 7A further including a means for coupling the micro-controller module with a means for locating the container handler;

FIG. 14B shows a detail flowchart of FIG. 8A further providing the micro-controller module with the coupled means for sensing the state of the container handler of FIGS. 6A and 7A;

FIG. 14C shows a detail of FIG. 8A further providing the micro-controller module with the coupled means for locating the container handler of FIG. 14A;

FIG. 15A shows the means for wirelessly communicating, including the means for wirelessly determining the location of the container handler;

FIG. 15B shows a detail of the program system of FIGS. 6A and 6B for determining and communicating the location of the container handler;

FIG. 16A shows the memory of FIG. 6A including a non-volatile memory;

FIG. 16B shows a detail flowchart of FIG. 8A for installing the program system of FIG. 6A;

FIGS. 17 to 20 show various embodiments of the status reporting device for the rubber tire gantry crane of FIG. 1 and the quay crane of FIG. 2;

FIGS. 21 to 23 show various embodiments of the status reporting device for the side picker of FIG. 3A, the reach stacker of FIG. 4A, the top loader of FIG. 4C, straddle carrier of FIG. 4D; and

FIGS. 24 and 25 shows various embodiments of the status reporting device for the UTR truck and/or bomb cart/chassis of FIG. 1.

#### DESCRIPTION OF THE PREFERRED EMBODIMENTS

The invention includes an apparatus and a method of making at least one, preferably many status reporting device 800 for at least one, preferably many container handler 78. The manufacturing proceeds in a modular, highly efficient manner, which is able to use a relatively small number of different parts to serve the needs of a wide variety of container handlers.

A container handler 78 will refer herein to a device, usually operated by a human operator, which moves a container 2 of at least twenty feet in length. International commerce primarily uses containers of approximately twenty feet to forty five feet in length. Containers when filled with cargo may weigh up to 110,000 pounds, or up to 50,000 kilograms. The width of the container 2 may be at least eight feet wide. The height of the container may be at least eight feet six inches.

As used herein, a container handler 78 will refer to at least one of the members of the container handler list 80 shown in FIG. 4B. The container handler list 80 includes, but is not limited to, the following.

The UTR truck 10, the bomb cart 14, and the Rubber Tire Gantry crane 20, often abbreviated RTG crane are shown in FIG. 1. Note that the bomb cart 14 is also known as a container chassis, when the container 2 is tied down. Within container terminals, containers are not typically tied down to bomb carts.

The quay crane 30 is shown in FIG. 2.

The side picker 40 is shown in FIG. 3A.

The reach stacker 46 is shown in FIG. 4A.

The top handler 50 is shown in FIG. 4C.

The straddle carrier 54 is shown in FIG. 4D.

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The chassis rotator 58. The chassis rotator is used to rotate the chassis used to haul one or more containers. Its operations and requirements are similar to other container handlers, except that its rectilinear position is fixed. More relevant for these container handlers is the use of its location 1900 as an angular measure of its orientation of the container 2. The means for determining 1500 the location 1900 consequently may use a shaft encoding, possibly an optical shaft encoder.

The rubber tire gantry crane 20 of FIG. 1 may be called a transfer crane and/or a TRANSTAINER™. The quay crane 30 of FIG. 2 is sometimes referred to as a PORTAINER™. The side picker 40 of FIG. 3A is also referred to as a side handler or a side hauler. The top loader 50 of FIG. 4C is also referred to as a top picker or top handler.

Some of these container handlers have the ability to lift and/or place a container 2. A container handler 78 able to lift and/or place the container is a member of the stacking handler list of FIG. 4B, which includes, but is not limited to, the following.

The rubber tire gantry 20 of FIG. 1 includes a rubber tire gantry spreader 22.

The quay crane 30 of FIG. 2 includes a quay crane spreader, which is outside the picture.

The side picker 40 of FIG. 3A includes a side picker spreader 42.

The reach stacker 46 of FIG. 4A includes a reach stacker spreader 48.

The top handler 50 of FIG. 4C includes a top handler spreader 52.

The straddle carrier 54 of FIG. 4D includes a straddle carrier spreader 56.

FIG. 3B shows a stack of containers including first container 60 to fourth container 66 defining what is referred to herein as a stacking height.

The stacking height of the first container 60 is usually denoted as one.

The stacking height of the second container 62 is two.

The stacking height of the third container 64 is three.

And the stacking height of the fourth container 66 is four. While this is a standard designation, any other designation may be used within a computer, such as numbering as follows, first container 60 as zero, second container 62 as one, third container 64 as two, and fourth container 66 as three.

In some situations, container stacks may preferably include more than four container stacked on top of each other, for example, up to seven containers high.

FIGS. 5A and 5B show two examples of a housing 3000 of the status reporting device 800 for use on various members of the container handler list 80.

The housing 3000 of FIG. 5A includes a housing mount 3002, by which it may be preferably attached to a rubber tire gantry crane 20 of FIG. 1 and/or quay crane 30 of FIG. 2. The housing 3000 may preferably contain at least part of the means for optical container code sensing 1230.

The housing 3000 of FIG. 5B preferably includes a display 3010. The housing 3000 may preferably be attached to any member of the container handler list 80.

FIG. 6A shows a system for making 100 a status reporting device 800 for a container handler 78 of FIGS. 13A and 13B. The container handler 78 is a member of the container handler list 80. Some preferred embodiments of the status reporting device 800 for specific members of the container handler list 80 are shown in FIGS. 17 to 25.

In FIG. 6A, the system for making **100** includes a means for providing **200** a micro-controller module **1000**.

The status reporting device **800** includes a first communicative coupling **1102** of the micro-controller module **1000** with a means for wirelessly communicating **1100**, and

The status reporting device **800** includes a second communicative coupling **1202** of the micro-controller module **1000** with a means for sensing state **1200** of at least one member of the container handler list **80** of FIG. 4B.

In FIG. 6A, the system for making **100** also includes means for installing **300** a program system **2000**. The program system **2000** is installed into **302** a memory **1020**.

The micro-controller module **1000** includes an accessible coupling **1022** of a computer **1010** with the memory **1020**.

The computer **1010** directs the activities of the micro-controller module **1000** through a program system **2000**.

The program system **2000** includes program steps residing in the memory **1020** as shown in FIGS. 6A and 16A.

The method of operating the status reporting device **800** will be discussed as implemented by the program system **2000**. One skilled in the art will recognize that alternative implementations, which may include, but are not limited to, finite state machines, neural networks, and/or inferential engines are possible, feasible, and in certain circumstances, potentially preferable.

A computer as used herein may include, but is not limited to, an instruction processor and/or a finite state machine, and/or an inferential engine, and/or a neural network. The instruction processor includes at least one instruction processing element and at least one data processing element, each data processing element controlled by at least one instruction processing element.

An embodiment of the computer, as used herein, may include not only what some would consider peripheral circuitry, which may include, but is not limited to, communications circuitry, memory, memory interface circuitry, clocking and timing circuitry, as well as signal protocol interface circuitry.

These circuits may be fabricated in the same package as the computer, sometimes on the same semiconductor substrate as the computer.

While some of these circuits may be discussed separately from the computer, this is done to clarify the operation of the invention and is not meant to limit the scope of the claims to mechanically distinct circuit components.

Embodiments of the status reporting device **800** may include determining the location **1900** of a container handler as shown in FIG. 6A.

These aspects will be discussed later regarding the means for determining **1500** the location **1900** of the container handler as in FIGS. 14A to 14C, 15B, 17, 18, 21, 22, and 24.

Other alternatives may include, but are not limited to, using a means for wirelessly communicating **1100** which includes a means for wirelessly determining **1510** for locating the container handler, as discussed in FIGS. 15A, 19, 20, 23, and 25. These aspects of the invention may not require the storage of the location **1900** in the computer **1010** of FIG. 6A.

Some of the following figures show flowcharts of at least one method of the invention, possessing arrows with reference numbers. These arrows will signify of flow of control and sometimes data supporting implementations including at least one program operation or program thread executing upon a computer,

at least one inferential link in an inferential engine, at least one state transitions in a finite state machine, and/or at least one dominant learned response within a neural network.

The operation of starting a flowchart is designated by an oval with the text "Start" in it, and refers to at least one of the following.

Entering a subroutine in a macro instruction sequence in a computer.

Entering into a deeper node of an inferential graph.

Directing a state transition in a finite state machine, possibly while pushing a return state.

And triggering a list of neurons in a neural network.

The operation of termination in a flowchart is designated by an oval with the text "Exit" in it, and refers to the completion of those operations, which may result in at least one of the following:

return from a subroutine return,

traversal of a higher node in an inferential graph,

popping of a previously stored state in a finite state machine, and/or

return to dormancy of the firing neurons of the neural network.

FIG. 6B shows the program system **2000** of FIG. 6A, which the means for installing **300** installed into **302** the memory **1020**.

Operation **2012** supports using the means for sensing state **1200** of FIG. 6A for sensing the state of the container handler **78** of FIGS. 13A and/or 13B, to create a sensed state **1800**.

Operation **2022** supports using the means for wirelessly communicating **1100** to communicate the sensed state **1800** of the container handler **78**.

One skilled in the art will recognize that the means for sensing state **1200** may further preferably include specific sensors and interfaces beyond those related with FIGS. 13A and/or 13B.

FIGS. 17 to 25 outline some variations of sensors, instrumentation and interfaces which may be preferred for various types of the container handler **78**, which are members of the container handler list **80** of FIG. 4B.

Because of the complexity of FIGS. 17 to 25, the label **1200** will not be found in the drawings, but will be called out in their discussion.

FIG. 7A shows a refinement of the status reporting device **800** of FIG. 6A. The micro-controller module **1000** further includes a computer communicative coupling **1032** of the computer **1010** with a Network Interface Circuit **1030**, denoted as (NIC).

FIG. 7A also shows a refinement of the means for providing **200** the micro-controller module **1000**. The means for providing **200** the micro-controller module **1000** further includes:

A means for coupling **210**, which creates the coupling **212** of the network coupling **1104** of the network interface circuit **1030** with the means for wirelessly communicating **1100**.

A means for sensor coupling **220**, which creates the sensor coupling **222** of the sensor coupling the micro-controller module **1000** to **1202** the means for sensing state **1200** of the container handler. This mechanism and process is similar to the various embodiments of the means for coupling **210** which creates the coupling **212**, which will be described in greater detail.

FIG. 7B shows a detail flowchart of operation **2022** of FIG. 6B further using the means for wirelessly communicating **1100**. Operation **2052** interacts via the computer communi-

cative coupling **1032** with the network interface circuit **1030** via the network coupling **1104** with the means for wirelessly communicating **1100** to communicate the sensed state **1800** for the container handler.

FIG. 7C shows a further, often preferred, embodiment of the system for making **100** the status reporting device **800** of FIGS. 6A and 7A.

The system for making **100** may include a second computer **500** at least partly directing the creation of the status reporting device **800**.

The second computer **500** may at least partly first direct **502** the means for providing **200** the micro-controller module **1000**.

The second computer **500** may at least partly second direct **504** the means for installing **300** the program system **2000**.

The communications coupling between the second computer **500** with the means for providing **200** and the means for installing **300** may be a shared coupling, and the first direct **502** and the second direct **504** may use an addressing scheme for message or communications addressed to these means.

In FIG. 7C, the system for making **100** further includes the following.

A second accessible coupling **512** of the second computer **500** with a second memory **510**.

A second program system **2500** includes program steps residing in the second memory **510**.

The second computer **500** is at least partly controlled by the program steps of the second program system **2500**, which are provided through the second accessible coupling **512** of the second memory **510**.

The second program system **2500** may be considered to embody the method of manufacture, by directing the means for providing **200** and the means for installing **300** to create the status reporting device **800**.

FIG. 8A shows a flowchart of the second program system **2500** of FIG. 7C, embodying certain aspects of the invention's method of making the status reporting device **800** of FIGS. 6A and 7A, which includes the following operations.

Operation **2512** directs the means for providing **200** to provide **202** the micro-controller module **1000** of FIGS. 6A and 7A.

Operation **2522** directs the means for installing **300** to install **302** the program system **2000** of FIGS. 6A, 7A, and 7B, into the memory **1020**.

In FIG. 8A, the operation **2512** directing the means for providing **200** to provide **202** the micro-controller module **1000** of FIGS. 6A and 7A may involve the following in certain preferred embodiments.

The act of providing the micro-controller module **1000** may include, but is not limited to, fetching the module into an assembly work station, and/or positioning it for attachment to cables and test instruments.

The micro-controller module **1000** is provided with a first communicative coupling **1102** with the means for wirelessly communicating **1100**.

The micro-controller module **1000** is also provided with a second communicative coupling **1202** to the means for sensing state **1200** for the container handler.

In FIG. 8A, the operation **2522** directing the means for installing **300** to install **302** the program system **2000** of FIGS. 6A, 7A, and 7B, into the memory **1020** may involve the following in certain preferred embodiments.

An accessible coupling **1022** of the memory **1020** and the computer **1010** supports the program system **2000** at least partly directing the computer **1010**.

In certain preferred embodiments, the program system **2000** is installed **302** from a program system library **2400**, as shown in FIG. 7C. The program system **2000** may be installed **302** using a wireline network interface circuit **1030**, and/or using the means for wirelessly communicating **1100**. The memory **1020** may preferably include at least one non-volatile memory component. The non-volatile memory component may preferably include a flash memory device. The installation may preferably include programming the flash memory component to install **302** the program system **2000**.

The program system library **2400** may include multiple versions of the program system **2000**, for use in controlling various embodiments of the status reporting device **800** created by the manufacturing process of the system for making **100**.

FIG. 8B shows a detail of operation **2512** of FIG. 8A further providing the micro-controller module **1000**. Operation **2552** supports creating the coupling **212** of the network interface circuit **1030** to **1104** the means for wirelessly communicating **1100**.

In FIGS. 7A and 8B, the network interface circuit **1030** may preferably support at least one wireline communications protocol via the network coupling **1104** with the means for wirelessly communicating **1100**.

The wireline communications protocol may support a version of at least one member of a serial protocol list **2100** shown in FIG. 8C, including the following.

A Synchronous Serial Interface protocol **2101**, sometimes abbreviated SSI.

An Ethernet protocol **2102**.

A Serial Peripheral Interface **2103**, sometimes abbreviated SPI.

An RS-232 protocol **2104**.

An Inter-IC protocol **2105**, sometimes abbreviated I2C.

An Universal Serial Bus protocol **2106**, sometimes abbreviated USB.

A Controller Area Network protocol **2107**, sometimes abbreviated CAN.

A Firewire protocol **2108**, which includes implementations the IEEE 1394 communications standard.

An RS-485 protocol **2109**.

An RS-422 protocol **2111**.

In FIGS. 6A, 7A and 7C, the means for wirelessly communicating **1100** may preferably support communicating using at least one version of at least one member of a wireless modulation-demodulation scheme list **2110** shown in FIG. 8D. The wireless modulation-demodulation scheme list **2110** includes, but is not limited to, the following.

A Time Division Multiple Access scheme **2112**, sometimes abbreviated TDMA.

A Frequency Division Multiple Access scheme **2114**, sometimes abbreviated FDMA.

And a Spread Spectrum Scheme **2115**, which may include variations on one or more of the following:

A Code Division Multiple Access scheme **2116**, sometimes abbreviated CDMA.

A Frequency Hopping Multiple Access scheme **2118**, sometimes abbreviated FHMA.

A Time Hopping Multiple Access scheme **2120**, sometimes abbreviated THMA.

And an Orthogonal Frequency Division Multiple access scheme **2122**, sometimes abbreviated OFDM.

FIG. 9A shows a refinement of part of the wireless modulation-demodulation scheme list **2110** of FIG. 8D, which includes the following.

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At least one version of the Time Division Multiple Access scheme **2112** (TDMA) may preferably include a GSM access scheme **2130**.

At least one version of the Frequency Division Multiple Access scheme **2114** (FDMA) may preferably include an AMPs scheme **2132**.

At least one version of the Code Division Multiple Access scheme **2116** (CDMA) may preferably include at least one member of the CDMA scheme list **2150**.

At least one version of the Orthogonal Frequency Division Multiple access scheme **2122** (OFDM) may preferably include at least one IEEE 802.11 access scheme **2134**. At least one version of the IEEE 802.11 access scheme **2134** may include the IEEE 802.11b access scheme **2136**. At least one version of the IEEE 802.11 access scheme **2134** may include the IEEE 802.11g access scheme **2135**.

At least one version of the Spread Spectrum Scheme **2115** uses the Ansi 371.1 scheme **2138** for radio frequency identification and/or location tags.

In FIG. 9A, the CDMA scheme list **2150** may preferably include, but is not limited to,

An IS-95 access scheme **2152**, which uses at least one spreading code to in modulating and demodulating an access channel.

A Wideband CDMA access scheme **2154**, sometimes abbreviated W-CDMA. W-CDMA schemes use not only a spreading code, but also a scattering code to modulate and demodulate an access channel.

FIG. 9B shows some refinements of the means for sensing state **1200** of the container handler of FIGS. 6A and 7A. Note that the preferred status reporting device **800** for various of the container handler **78** may include one or more of the means for sensing state **1200** shown in this Figure. The means for sensing state **1200** of the container handler may preferably include at least one of the following

A means for sensing operator identity **1210**, which provides **1212** a sensed operator identity **1214**.

A means for sensing container presence **1220**, which second provides **1222** a sensed container present **1224**.

A means for optical container code sensing **1230**, which third provides **1232** an optical container characteristic **1234**.

A means for radio frequency tag sensing **1250** of a radio frequency tag on the container **2** fourth providing **1252** a container radio frequency tag **1254**.

A means for container stack height sensing **1260** of the container **2** fifth providing **1262** a container stack height **1264**. In certain embodiments the means for container stack height sensing **1260** may preferably include a cam switch.

At least one means for sensing a machine state list member **1270** of the container handler, sixth providing **1272** a machine state list member **1274** of the machine state list **1850**, shown in FIG. 10E.

At least one crane sensor means list member **1280** seventh providing **1282** at least one crane state list member **1284** of a crane state list **1400** of FIG. 12B. The crane sensor means list member **1280** is a member of the crane sensor means list **1300** shown in FIG. 12A.

A means for sensing container size **1216** seventeenth providing **1218** a container size **1226**. The container size **1226** may preferably be denoted similarly to the spreader state list **1420** of FIG. 12D. In certain embodiments, for example for use on a UTR truck **10**, the means for sensing container size **1216** may include an ultrasonic sensor to estimate the container size on the back of

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a bomb cart **14**. The ultrasonic sensors measures the delay in an echo from the side of the container **2** to estimate its container size **1226**.

A means for sensing container weight **1228** eighteenth providing **1240** a container weight **1242**.

And a means for sensing container damage **1244** nineteenth providing **1246** a container damage estimate **1248**.

In FIG. 9B, the various combinations of some or all of the providings may be similarly implemented.

Among providings similarly implemented, these providings may share a single communication mechanism with the computer **1010**.

Among providings similarly implemented, these providings may use multiple communication mechanisms with the computer **1010**.

In FIG. 9B, some or all of the providings may be distinctly implemented.

In FIG. 9B, the providings may include at least one instance of the following:

provides **1212** a sensed operator identity **1214**,

second provides **1222** a sensed container present **1224**,

third provides **1232** an optical container characteristic **1234**,

fourth providing **1252** a container radio frequency tag **1254**,

fifth providing **1262** a container stack height **1264**,

sixth providing **1272** a machine state list member **1274**,

seventh providing **1282** at least one crane state list member **1284** of the crane state list **1400** shown in FIG. 12B,

seventeenth providing **1218** a container size **1226**,

eighteenth providing **1240** a container weight **1242**, and

nineteenth providing **1246** a container damage estimate **1248**.

By way of example, the seventh providing **1282** of FIG. 9B, for a rubber tire gantry crane **20** or a straddle carrier **54**, may preferably use at least one of the Synchronous Serial Interface protocol **2101**, the RS-232 Protocol **2104**, the RS-422 Protocol **2111** and/or the RS-485 Protocol **2109**.

The crane sensor means list member **1280** may preferably include the means for sensing trolley position **1360** fourteenth providing **1362** a trolley position **1364** as in FIG. 12A.

The crane sensor means list member **1280** may preferably include the means for sensing hoist height **1370** fifteenth providing **1372** a hoist height **1374**.

The means for sensing trolley position **1360** and/or the means for sensing hoist height **1370** may preferably include a rotary absolute optical encoder with either a hollow shaft or standard shaft.

FIG. 10A shows some refinements of the sensed state **1800** of FIGS. 6A and 7A based upon the means for sensing state **1200** of FIG. 9B. The sensed state **1800** may preferably include at least one of the following,

The sensed operator identity **1214**.

The sensed container present **1224**. The sensed container present **1224** may preferably be a boolean value of true or false.

The optical container characteristic **1234**.

The container radio frequency tag **1254**.

The container stack height **1264**. The container stack height **1264** may be interpreted as in the discussion of FIG. 3B.

At least one instance of at least one machine state list member **1274**.

At least one of the crane state list members **1284**.

The container size **1226**.

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The container weight **1242**.

The container damage estimate **1248**.

The optical container characteristic **1234** of FIGS. 9B and **10A** may preferably include at least one instance of a member of a container code characteristic list **1700**, shown in FIG. **10B**, which may preferably include

a container code text **1702**,

a view **1704** of the container code **4** of the container **2**, and  
a compression **1706** of the view **1704** of the container code **4** of the container **2**.

FIGS. **11A** and **11B** show examples of the view **1704** in FIG. **10B**, of the container code **4** optically viewed on the side of the container **2** of FIGS. **1**, **3A**, and **4A**. The view **1704** of the container code **4** may preferably and alternatively be viewed on any of the vertical sides of the container **2**.

The compression **1706** of the view **1704** may include, but is not limited to, a still frame compression and/or a motion sequence compression of a succession of frames of views.

The compression **1706** may be at least partly the result of applying a two dimensional (2-D) block transform, such as the 2-D Discrete Cosine Transform (DCT) and/or a 2-D wavelet filter bank.

Alternatively, the compression **1706** may be at least partly the result of a fractal compression method.

FIG. **11C** shows an example of the container code text **1702** of FIG. **10B**.

The container code text **1702** may be at least partly the result of optical character recognition applied to the view **1704** of FIG. **11B**.

The means for optical container code sensing **1230** of FIG. **9B** may include optical character recognition capabilities, which may be embodied as a separate optical character recognition hardware module or as a separate optical character recognition program system.

The separate optical character recognition hardware module may reside within the means for optical container code sensing **1230** and/or may be coupled to the means for optical container code sensing **1230**.

The separate optical character recognition program system may reside within the means for optical container code sensing **1230** and/or may be coupled to the means for optical container code sensing **1230**.

The status reporting device **800** of FIG. **6A** may include an optical characteristic system as the means for optical container code sensing **1230** of FIG. **9B**, in housing **3000** of FIGS. **1**, **2**, **5A** and **5B**.

The means for optical container code sensing **1230** may include at least one and preferably two of the video imaging device **1238** of FIG. **10C**, housed in a first housing **3100** and a second housing **3110** as in FIGS. **1** and **2**.

The first housing **3100** and the second housing **3110** may be mechanically coupled to a container handler **20** or **30** as in FIGS. **1** and **2**.

The status reporting device **800** may also include at least one, and preferably more than one, light **3120**. The lights **3120** may be controlled through interaction with the invention.

The mechanical coupling of the means for optical container code sensing **1230** to the rubber tire gantry crane **20** may preferably include a mechanical shock absorber to improve reliability.

FIG. **10C** shows some preferred alternative embodiments of the means for optical container code sensing **1230** of FIG. **9B**. The means for optical container code sensing **1230** of the

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container code **4** on the container **2** may preferably include any combination of the following.

A video interface **1236** to receive at least one optical container characteristic **1234** of the container code **4**.

At least one video imaging device **1238** to create at least one optical container characteristic **1234** of the container code. The video imaging device **1238** may be in a separate housing and/or location as shown by the first housing **3100** and/or the second housing **3110** in FIGS. **1**, **2**, and **5A**.

At least one image processor **1239** may process and/or create at least one of the optical container characteristic **1234**.

The video imaging device **1238** may belong to a list including at least a video camera, a digital video camera, and a charged coupled array.

The video imaging device **1238** may further include any of the following: a computer, a digital memory, an instance of the image processor **1239** and/or a flash lighting system.

FIG. **10D** shows a further preferred embodiment of the means for container stack height sensing **1260**, including a stacking height sensor interface **1266** to a stacking height sensor on the container handler **78**. One stacking height sensor, which may be preferred, is a draw wire encoder.

The draw wire encoder may be preferred when the container handler is at least one of the following: the rubber tire gantry crane **20**, the side picker **40**, the top loader **50**, the reach stacker **46**, and/or the straddle carrier **54**.

Alternatively, the stacking height sensor may be an absolute/hollow shaft encoder.

FIG. **10E** shows a preferred embodiment of the machine state list **1850**. The machine state list **1850** may include, but is not limited to,

a reverse motion **1852**,

a frequent stops count **1854**,

a collision state **1856**,

a fuel level **1858**,

a compass reading **1860**,

a wind speed **1862**. In certain embodiments, the wind speed may further indicate a wind direction,

a vehicle speed **1864**, and

a vehicle braking system state **1866**.

In some preferred embodiments, the means for sensing a machine state list member **1270**, the machine state list member **1274** includes the vehicle speed **1864**, may preferably include a drive shaft sensor counting the drive shaft revolutions.

FIG. **12A** shows some details of the crane sensor means list **1300** related to at least one instance of the crane sensor means list member **1280** of FIG. **9B**. The crane sensor means list **1300** preferably includes at least one of the following

A means for twistlock sensing **1310** eighth providing **1312** a twistlock sensed state **1314**.

The means for spreader sensing **1320** to ninth provide **1322** a spreader sensed state **1324**.

The means for sensing container landing **1330** to tenth provide **1332** a sensed landing state **1334**.

The means for sensing trolley position **1360** fourteenth providing **1362** a trolley position **1364**.

The means for sensing hoist height **1370** fifteenth providing **1372** a hoist height **1374**.

The means for sensing trolley position **1360** and/or the means for sensing hoist height **1370** may preferably include a rotary absolute optical encoder with either a hollow shaft or standard shaft.



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In FIG. 12A, the twistlock sensed state **1314**, preferably, is a member of a twistlock state list **1410** shown in FIG. 12C. FIG. 12C shows the twistlock state list **1410** including a twistlock-on state **1412** and a twistlock-off state **1414**.

In FIG. 12A, the spreader sensed state **1324**, preferably is a member of a spreader state list **1420** shown in FIG. 12D. FIG. 12D shows the spreader state list **1420** including a ten foot container spread **1421**, a twenty foot container spread **1422**, a thirty foot container spread **1428**, a forty foot container spread **1424**, and a forty-five foot container spread **1426**.

Various embodiments may support the spreader sensed state **1324** limited to a subset of the spreader state list **1420**.

By way of example, in certain preferred embodiments, the spreader sensed state **1324** may be limited to a subset of the spreader state list **1420** consisting of the twenty foot container spread **1422** and the forty foot container spread **1424**.

In FIG. 12A, the sensed landing state **1334**, preferably, is a member of a landing state list **1430** shown in FIG. 12E. FIG. 12E shows the landing state list **1430** including a landed state **1432** and a not-landed state **1434**.

FIG. 12B shows some details of the crane state list **1400** related to the crane state list member **1284** of FIGS. 9B and 10A. The crane state list **1400** preferably includes at least one of the following

The twistlock sensed state **1314**,

The spreader sensed state **1324**,

The sensed landing state **1334**.

FIG. 13A shows a refinement of the status reporting device **800** of FIGS. 6A and 7A where the means for sensing state **1200** includes a crane spreader interface connection **1340**.

The crane spreader interface connection **1340** preferably provides at least one member of the crane state list **1400** as shown in FIG. 12B.

The crane spreader interface connection **1340** eleventh provides **1344** the twistlock sensed state **1314**.

The crane spreader interface connection **1340** twelfth provides **1346** the spreader sensed state **1324**.

The crane spreader interface connection **1340** thirteenth provides **1348** the sensed landing state **1334**.

FIG. 13A also shows the status reporting device **800** with the means for sensing state **1200** of the container handler **78** including a crane sensor coupling **1342** of the computer **1010** of FIGS. 6A and 7A to the crane spreader interface connection **1340**.

The crane sensor coupling **1342** may preferably include conversion circuitry interfaced to parallel input and/or output ports of the computer **1010**. The conversion circuitry may interface AC lines through relays.

In certain embodiments, the crane sensor coupling **1342** may be included in the second communicative coupling **1202** of the micro-controller module **1000** with the means for sensing state **1200**.

Alternatively, the crane sensor coupling **1342** may not be included in the second communicative coupling **1202** of the micro-controller module **1000** with the means for sensing state **1200**.

By way of example, the crane spreader interface connection **1340** of FIG. 13A may contain the spreader sensed state **1324** as two signals.

The two signals are the “spreader is at least twenty foot”, and the “spreader is at forty foot”.

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If the “spreader is at least twenty foot” is true and the “spreader is at forty foot” is false, then the sensed spreader state **1324** indicates the crane spreader is set for twenty foot.

If the “spreader is at least twenty foot” is true and the “spreader is at forty foot” is true, then the sensed spreader state **1324** indicates the crane spreader set for forty foot.

By way of example, the crane spreader interface connection **1340** of FIG. 13A may contain the spreader sensed state **1324** as three signals.

The two signals are the “spreader is at least twenty foot”, the “spreader is at forty foot”, and the “spreader is at least forty-five foot”.

If the “spreader is at least twenty foot” is true, the “spreader is at forty foot” is false, and the “spreader is at least forty-five foot” is false, then the sensed spreader state **1324** indicates the crane spreader is set for twenty foot.

If the “spreader is at least twenty foot” is true, the “spreader is at forty foot” is true, and the “spreader is at least forty-five foot” is false then the sensed spreader state **1324** indicates the crane spreader set for forty foot.

If the “spreader is at least twenty foot” is true, the “spreader is at forty foot” is true, and the “spreader is at least forty-five foot” is true then the sensed spreader state **1324** indicates the crane spreader set for forty-five foot.

In FIG. 13A, some or all of the providings may be similarly implemented. Among those providings similarly implemented, they may use the same of different mechanisms to provide. Alternatively, some of the providings may be distinctly implemented. The providings of FIG. 13A include

The eleventh provides **1344** the twistlock sensed state **1314**.

The twelfth provides **1346** the spreader sensed state **1324**.

The thirteenth provides **1348** the sensed landing state **1334**.

FIG. 13B shows a refinement of the status reporting device **800** of FIGS. 6A and 7A, with the means for sensing state **1200** of the container handler **78**, including a Programmable Logic Controller **1350**, which is sometimes denoted PLC.

The Programmable Logic Controller **1350** preferably provides at least one member of the crane state list **1400** as shown in FIG. 12B.

Preferably, the Programmable Logic Controller **1350** may fourteenth provide **1354** the twistlock sensed state **1314**.

Preferably, the Programmable Logic Controller **1350** may fifteenth provide **1356** the spreader sensed state **1324**.

Preferably, the Programmable Logic Controller **1350** may sixteenth provide **1358** the sensed landing state **1334**.

FIG. 13B also shows the status reporting device **800** including a second crane sensor coupling **1352** of the computer **1010** of FIGS. 6A, 7A and 13A with the Programmable Logic Controller **1350**.

The second crane sensor coupling **1352** may preferably include a serial communications coupling **1352**.

The serial communications coupling **1352** preferably supports a version of at least one member of a serial protocol list **2100** of FIG. 8C.

In FIG. 13B, some or all of the providings may be similarly implemented. Among those providings similarly implemented, they may use the same of different mechanisms to provide. Alternatively, some of the providings may be distinctly implemented. The providings of FIG. 13B include

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The fourteenth provide **1354** the twistlock sensed state **1314**.

The fifteenth provide **1356** the spreader sensed state **1324**.

The sixteenth provide **1358** the sensed landing state **1334**.

In FIGS. **13A** and **13B**, the container handler **78** may preferably be a version of a member of the container handler list **80** of FIG. **4B**. The container handler **78** may also be an assembly of two or more members of the container handler list **80**. By way of example, the container handler **78** may include the UTR truck **10** of FIG. **1** attached to the Bomb cart **14**. In certain situations, the UTR truck **10** may be attached to an over the road chassis.

FIG. **14A** shows the means for providing **200** of FIGS. **6A** and **7A** further including a means for location coupling **230**. The means for location coupling **230** assembles **232** the micro-controller module **1000** with a means for determining **1500** location the container handler.

FIG. **14B** shows a detail flowchart of operation **2512** of FIG. **8A** further providing the micro-controller module **1000** with the coupled means **1200** for sensing the state of the container handler of FIGS. **6A** and **7A**. Operation **2562** supports providing the micro-controller module **1000** with the second communicative coupling **1202** to the means for sensing state **1200** of the container handler.

FIG. **14C** shows a detail of operation **2512** of FIG. **8A** further providing the micro-controller module **1000** coupled with the means for determining **1500** the location the container handler of FIG. **14A**. Operation **2572** supports providing the micro-controller module **1000** communicatively coupling **1502** to a means for determining **1500** the location of the container handler.

In FIG. **14A**, the means for determining **1500** may include one or more of the following:

An interface to a Global Positioning System (GPS).

An interface to a Differential Global Positioning System (DGPS).

A means for wirelessly determining location, such as by use of a local wireless network providing timed signal bursts from multiple antenna sites within the local wireless network.

A radio location-tag unit.

As used herein, GPS is a satellite communications system, which supports determining the location of a receiver. DGPS is a refinement of the GPS using an earth-based reference station to support positional accuracy to within a meter.

FIG. **15A** shows the means for wirelessly communicating **1100** including the means for wirelessly determining **1510** the location of the container handler. The means for wirelessly determining **1510** may include one or more of the following:

An interface to the Global Positioning System (GPS).

An interface to the Differential Global Positioning System (DGPS).

Alternatively, the means for wirelessly determining **1510** may provide timed signal bursts to multiple antenna sites within the local wireless network to support the wireless network determining the location of itself. This means for wirelessly determining **1510** may not require the use or storage of an estimate of the location **1900** in the memory **1020** accessed **1022** by the computer **1010**, as shown in FIG. **6A**.

FIG. **15B** shows a detail of the program system **2000** of FIGS. **6A** and **6B** for determining and communicating the location of the container handler **78**.

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Operation **2072** supports using the means **1500** of FIG. **14A** for locating the container handler **78** to, at least partly, determine the location **1900** of the container handler **78**.

Operation **2082** uses the means for wirelessly communicating **1100** to communicate the location **1900**.

In FIG. **15A**, the means for wirelessly communicating **1100** may further include a radio location-tag unit.

In certain preferred embodiments, the radio location-tag unit may act as the means for wirelessly determining **1510** the location **1900** of the container handler **78**.

The radio location-tag unit may further support a national and/or international standard, which may include, but is not limited to, a version of ANSI 371.1 standard for radio location tags.

In such embodiments, the local computer **1010** may not require the location **1900** present in memory **1020**, as shown in FIG. **6A**.

In such embodiments, the need for the program system **2000** to determine location may be non-existent, removing the presence of the operation of FIG. **15B**.

FIG. **16A** shows the memory **1020** of FIG. **6A** including a non-volatile memory **1024**. The computer **1010** may preferably access **1022** the non-volatile memory **1024**, similarly to the discussion of FIG. **6A**. The non-volatile memory **1024** may include at least part of the program system **2000**.

FIG. **16B** shows a detail flowchart of operation **2522** of FIG. **8A** further installing the program system **2000** of FIG. **6A**.

Operation **2592** supports altering at least part of the non-volatile memory **1024** of FIG. **16A** to install at least part of at least one program step of the program system **2000**.

Operation **2602** supports installing a memory module including at least part of at least one of the program steps residing in the non-volatile memory **1024** to create at least part of the memory **1020** accessed **1022** by the computer **1010**.

FIGS. **17** to **20** show various status reporting devices **800** for the rubber tire gantry crane **20** of FIG. **1**. Similar embodiments are useful with the quay crane **30** of FIG. **2**. In FIGS. **17** to **20**, the means for sensing state **1200** is disclosed in terms of the details of its contents and communications.

FIG. **17** shows the status reporting device **800** communicating through couplings with

The means for wirelessly communicating **1100**,

The display **3010**, may preferably be a Liquid Crystal Display, and

The means for sensing state **1200** includes the following:

The means for sensing operator identity **1210**,

The means for container stack height sensing **1260**,

The means for sensing a machine state list member **1270**,

The crane spreader interface connection **1340**,

The means for determining **1500** location, further including a Differential Global Positioning System (DGPS), and

A second means for determining **1500-B** location, which preferably includes a means for sensing laser trolley position. Alternatively, this may incorporate a draw wire and/or rotary encoder.

In FIG. **17**, the means for sensing a machine state list member **1270** provides the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, the wind speed **1862**, and the vehicle speed **1864**.

In FIGS. **17** and **20**, the means for sensing state **1200** also provides, via the crane sensor coupling **1342**, the following to the computer **1010**:

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The twistlock sensed state **1314**,  
The spreader sensed state **1324**, which may further preferably include  
the spreader sense state at twenty foot **1324-20**, and  
the spread sense state at forty foot **1324-40**, and  
the sensed landing state **1334**.

FIG. **18** shows the status reporting device **800** communicates via couplings with

The means for wirelessly communicating **1100**, which preferably includes a wireless modem preferably supporting a version of the IEEE 802.11 access scheme **2134**, preferably the IEEE 802.11b access scheme **2136**. Alternatively, the wireless modem may support an Radio Frequency IDentification (RF ID) protocol.

The display **3010**, and

The means for sensing state **1200**, which preferably includes the following

The means for sensing operator identity **1210**,

The means for container stack height sensing **1260**,

The means for sensing a machine state list member **1270**, which provides the frequent stops count **1854**, the collision state **1856**, the fuel level **1858** and the wind speed **1862**.

The Programmable Logic Controller **1350**, and

The means for determining **1500** location, preferably using the Differential Global Positioning System (DGPS) of FIG. **14A**,

In FIG. **18**, the computer **1010** couples through the Programmable Logic Controller **1350** with the following:

at least one means for container stack height sensing **1260**, and

a second means for determining **1500-B** location, which preferably includes a means for sensing laser trolley position.

FIG. **19** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**, which further includes the means for wirelessly determining **1510** location of FIG. **15A**. The means for wirelessly determining **1510** may preferably include a radio frequency tag device.

The display **3010**.

And the means for sensing state **1200** which includes

The means for container stack height sensing **1260**,

The Programmable Logic Controller **1350**.

The means for sensing a machine state list member **1270**, which preferably provides the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, and the wind speed **1862**.

The means for sensing operator identity **1210**, similar to **1210** of FIGS. **17** and **18**.

FIG. **20** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100** may preferably include the means for wirelessly determining **1510** location of FIG. **15A**, which may preferably include a radio frequency tag device.

The display **3010**.

And the means for sensing state **1200** which includes

The means for sensing operator identity **1210**,

The means for container stack height sensing **1260**,

The crane spreader interface connection **1340**,

The second means for determining **1500-B** location, and

The means for sensing a machine state list member **1270**, which provides the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, the wind speed **1862**, and vehicle speed **1864**.

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In FIGS. **17** to **19**, a second means **1500-B** for determining the location of the container handler is used. The second means **1500-B** may preferably be a trolley position sensor, which may be laser based. The second means **1500-B** may preferably communicatively couple **1502-B** via an RS-232 interface with the status reporting device **800**.

FIGS. **17** to **23** show the means for container stack height sensing **1260**.

Preferably, the means for container stack height sensing **1260** may include at least one cam shaft and/or at least one hoist position encoder when used with the rubber tire gantry crane **20** of FIG. **1**.

Preferably, the means for container stack height sensing **1260** may include at least one cam shaft and/or at least one hoist position encoder when used with the quay crane **30** of FIG. **2**.

These interact with one or more sensors of the sensor hoist-stack position to sense the stack height for a rubber tire gantry crane **20** or quay crane **30**.

The means for sensing the stack height **1260** may involve as many as eight separate sensor states, which may indicate whether their respective stack location is occupied. Containers may be preferably stacked as high as seven containers.

FIGS. **21** to **23** show various status reporting devices **800** for use with some or all of the following container handlers **78**, which are members of the container handler list **80** of FIG. **4B**:

The side picker **40** shown in FIG. **3A**.

The reach stacker **46** shown in FIG. **4A**.

The top handler **50** shown in FIG. **4C**.

The straddle carrier **54** shown in FIG. **4D**.

In FIGS. **21** to **23**, the means for sensing state **1200** is disclosed in the details of its contents and communications.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the side picker **40**, the top handler **50** and/or the straddle carrier **54**, as well as the status reporting device **800** of FIGS. **17** to **20**, for use with the rubber tire gantry crane **20**, may sense the following.

The length of time the vehicle has run since it was started.

The compass reading **1860**.

When the spreader has landed on a container **2** as the sensed landing state **1334**.

When the spreader has locked on the container.

The container size **1226**, which is preferably one of the members of the spreader state list **1420** of FIG. **12D**. Further, the container size may preferably be one of the twenty foot container spread **1422**, the forty foot container spread **1424** and the forty-five foot container spread **1426**.

The container stack height **1264** may preferably range from one to seven containers in height. This may be preferably be measured in feet.

The reverse motion **1852**.

The fuel level **1858** may be optionally provided.

And the sensed operator identity **1214** may be optionally provided.

In certain embodiments, the status reporting device **800** may use the means for wirelessly communicating **1100** instead of the means for determining **1500** the location **1900**. The means for wirelessly communicating **1100** may sensed by an external radio system to determine the container handler location. This may be preferred in terms of the cost of production of the status reporting device.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the side picker **40**,

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the top handler **50** and/or the straddle carrier **54**, as well as the status reporting device **800** of FIGS. **17** to **20**, for use with the rubber tire gantry crane **20**, may implemented to include the following.

The means for spreader sensing **1320** may include a magnetic proximity switch on and/or near the status reporting device **800**.

The reverse sensor may be communicatively coupled with the reverse buzzer on the vehicle.

The sixth providing **1272** of the compass reading **1860** may use the RS-422 protocol **2111**.

The means for sensing container landing **1330** may include a proximity switch on and/or near the status reporting device **800**.

The means for wirelessly communicating **1100** may be used to provide location of the vehicle. It may be further preferred that there are multiple means for wirelessly communicating, which may further preferably embody a radio frequency tag technology, including a version of the ANSI 371.1 scheme **2138**. The radio frequency tag technology may preferably be compatible with the WHERENET™ products.

The first communicative coupling **1102** of the means for wirelessly communicating **1100** and the micro-controller module **1000** may use the RS-485 protocol **2109**.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the side picker **40** and/or the top handler **50**, may implemented to further include the following.

The means for container stack height sensing **1260** may include a draw wire encoder. The fifth providing **1262** of the container stack height **1264** may preferably use the RS-422 protocol **2111**.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the straddle carrier **54**, as well as the status reporting device **800** of FIGS. **17** to **20**, for use with the rubber tire gantry crane **20**, may implemented to include the following.

The means for sensing hoist height **1370** may include a hollow shaft or a shafted optical absolute encoder. The fifteenth providing **1372** of the hoist height **1374** may preferably use the RS-422 protocol **2111** and/or the Synchronous Serial Interface protocol **2101**.

The means for sensing trolley position **1360** may include a hollow shaft or a shafted optical absolute encoder. The fourteenth providing **1362** of the trolley position **1364** may preferably use the RS-422 protocol **2111** and/or the Synchronous Serial Interface protocol **2101**.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the side picker **40**, the top handler **50** and/or the straddle carrier **54**, as well as of FIGS. **17** to **20** for the rubber tire gantry crane **20**, may be implemented using a programmable logic controller **1350** as in FIG. **138**. The following may be preferred in such situations.

The sixth providing **1272** of the compass reading **1860** may use the RS-422 protocol **2111**.

The first communicative coupling **1102** of the means for wirelessly communicating **1100** and the micro-controller module **1000** may use the RS-485 protocol **2109**.

In certain preferred embodiments, the status reporting device **800** of FIGS. **21** to **23**, for use with the side picker **40**, the top handler **50**, and/or the straddle carrier **54**, as well as of FIGS. **17** to **20** for the rubber tire gantry crane **20**, may use a second display **3020**.

It may be preferred to send the human operator messages that are displayed on the second display. These messages

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may include directions to pickup a container **2** from a communicated location in the terminal yard.

Preferably, the means for wirelessly communicating **1100** supports a bi-directional communications protocol. The bi-directional communications protocol may preferably support a version of the IEEE 802.11 access scheme **2134**.

The bi-directional communications protocol may further support the reprogramming of non-volatile memory **1024**.

A location tag associated with the vehicle may be commanded to blink.

The use of a display **3010** supporting operator interactions may require a bi-directional communications protocol.

FIG. **21** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**.

The display **3010**.

The second display **3020**.

And the means for sensing state **1200**.

In FIG. **21**, the means for sensing state **1200** preferably includes

The means for sensing operator identity **1210**,

The means for sensing container presence **1220**,

The means for optical container code sensing **1230**,

The means for sensing a machine state list member **1270**, which provides the reverse motion **1852**, the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, the compass reading **1860**, and the vehicle speed **1864**,

The Programmable Logic Controller **1350**, and

The means for determining **1500** location.

In FIGS. **18**, **19**, and **21**, the Programmable Logic Controller **1350** further provides the computer **1010**, via the second crane sensor coupling **1352**, with the following:

The twistlock sensed state **1314**,

By way of example, the spreader sensed state **1324**, may further preferably include the spreader sense state at twenty foot **1324-20**, and the spread sense state at forty foot **1324-40**, and

the sensed landing state **1334**.

The spreader sensed state **1324** may include other sizes, examples of which are shown in the spreader state list **1420** of FIG. **12D**.

In FIGS. **18**, **19**, and **21**, the Programmable Logic Controller **1350** further provides the computer **1010**, via the second crane sensor coupling **1352**, with the states of the means for container stack height sensing **1260**. The Programmable Logic Controller **1350** may also sometimes preferably provide the spreader sensed state **1324**.

FIG. **22** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**.

The display **3010**.

The second display **3020**.

And the means for sensing state **1200**.

In FIG. **22**, the means for sensing state **1200** preferably includes

The means for sensing operator identity **1210**,

The means for sensing container presence **1220**,

The means for optical container code sensing **1230**,

The means for container stack height sensing **1260**,

The means for sensing a machine state list member **1270**, which provides the reverse motion **1852**, the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, and the compass reading **1860**, and

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The twistlock sensed state **1314**, the spreader sensed state **1324**, which may further preferably include the spreader sense state at twenty foot **1324-20**, and the spread sense state at forty foot **1324-40**, and the sensed landing state **1334**. The spreader sensed state **1324** may include other sizes, examples of which are shown in the spreader state list **1420** of FIG. **12D**.

The means for determining **1500** location.

FIG. **23** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**.

The display **3010**.

The second display **3020**.

And the means for sensing state **1200**.

In FIG. **23**, the means for sensing state **1200** preferably includes

The means for sensing operator identity **1210**,

The means for sensing container presence **1220**,

The means for optical container code sensing **1230**,

The means for container stack height sensing **1260**,

The means for sensing a machine state list member **1270**, which provides the reverse motion **1852**, the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, the compass reading **1860**, and the vehicle speed **1864**, and

The twistlock sensed state **1314**, the spreader sensed state **1324**, which may further preferably include the spreader sense state at twenty foot **1324-20**, and the spread sense state at forty foot **1324-40**, and the sensed landing state **1334**.

The spreader sensed state **1324** may include other sizes, examples of which are shown in the spreader state list **1420** of FIG. **12D**.

FIGS. **24** and **25** show various embodiments of the status reporting device **800** for the UTR truck **10** of FIG. **1**. In these Figures the means for sensing state **1200** is disclosed in the details of its contents and communications. The UTR truck may be attached to the bomb cart **14**, or a chassis **14**, where the container **2** may be tied down.

FIG. **24**, shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**.

The display **3010**.

And the means for sensing state **1200**.

In FIG. **24**, the means for sensing state **1200** preferably includes

The means for sensing operator identity **1210**.

The means for sensing container size **1216**. This may preferably use an ultrasonic sensor.

The means for sensing container presence **1220**.

The means for optical container code sensing **1230**.

The means for sensing a machine state list member **1270**, which provides the reverse motion **1852**, the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, and the vehicle speed **1864**. It may be preferred that the means for sensing not include the wind speed **1862**, as shown.

And a fifth wheel engage/disengage proximity sensor.

One alternative embodiment of the status reporting device **800** for a Quay crane **30** and/or the RTG crane **20** may preferably include an interface to the programmable logic controller **1350** using a Wheretag.

FIG. **25** shows the status reporting device **800** communicating via couplings with

The means for wirelessly communicating **1100**, preferably implemented using the means for wirelessly determining **1510**.

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The display **3010**.

And the means for sensing state **1200**.

In FIG. **25**, the means for sensing state **1200** preferably includes

The means for sensing operator identity **1210**.

The means for sensing container presence **1220**.

The means for sensing a machine state list member **1270**, which provides the reverse motion **1852**, the frequent stops count **1854**, the collision state **1856**, the fuel level **1858**, and the vehicle speed **1864**. It may be preferred that the means for sensing not include the wind speed **1862**, as shown.

And a fifth wheel engage/disengage proximity sensor.

The status reporting device **800** used on the bomb cart **14** and/or the chassis **14** may preferably resemble the status reporting device **800** for the UTR truck **10** shown in FIGS. **24** and **25** without those features which

sense an engine and/or its fuel, as well as,

sense the presence and/or identity of an operator.

The status reporting device **800** may also lack the means for optical container code sensing **1230**.

The status reporting device **800** of FIGS. **24** and/or **25**, for the UTR truck **10** may preferably operate as follows.

The micro-controller module **1000** may sense how long the UTR truck **10** has been running.

The micro-controller module **1000** may sense when the fifth wheel is engaged.

The micro-controller module **1000** may sense when the brakes are applied.

The micro-controller module **1000** may sense when the container **2** is a forty foot container.

The micro-controller module **1000** may sense when the container **2** is a twenty foot container and positioned in the front or back of a bomb cart **14**.

The micro-controller module **1000** may sense when the container **2** is on a chassis.

The micro-controller module **1000** may sense the compass reading **1860**.

Optionally, the micro-controller module **1000** may sense the fuel level **1858**.

Optionally, the micro-controller module **1000** may receive the sensed operator identity **1214**.

The means for wirelessly communicating **1100** may interface with the WHERENET™ radio tag system.

The means for wirelessly communicating **1100** may further be a WHERENET tag.

Communication through the means for wirelessly communicating **1100** may preferably occur when a container is engaged, a container is gained or leaves a bomb cart **14**, and/or when the UTR truck **10** starts to move.

In certain embodiments, the status reporting device **800** may use the means for wirelessly communicating **1100** instead of the means for determining **1500** the location **1900**. The means for wirelessly communicating **1100** may be sensed by an external radio system to determine the container handler location. This may be preferred in terms of the cost of production of the status reporting device.

The status reporting device **800** of FIGS. **24** and/or **25**, for the UTR truck **10** may preferably include the following sensor interfaces.

The fifth wheel engage-disengage may be sensed by a magnetic proximity switch.

The vehicle speed **1864** and/or movement may be sensed by the number of revolutions of the driveshaft.

The compass reading **1860** may interface using the RS-422 protocol **2111**.

The container presence may preferably use an ultrasonic sonar with a four to twenty milliAmp (mA) analog output. This is measured by the micro-controller module **1000** to determine the distance.

Alternatively, the container presence may use a laser to determine distance.

The means for wirelessly communicating **1100** may be coupled to the micro-controller module **1000** using the RS-422 protocol **2111**.

The determination of location may be achieved by the means for wirelessly communicating **1100**, particularly implementing the WHERENE™ radio tag.

The radio tag may further be commanded to blink.

The reverse motion sensor may be based upon the reverse motion buzzer of the UTR truck **10**.

In FIGS. **5B**, and **17** to **25**, the display **3010** is shown.

The display **3010** may communicate directly with the computer **1010**, or communicate through one of the Network Interface Circuits (NICs).

The display **3010** may preferably be a Liquid Crystal display. However, one skilled in the art will recognize that there are many alternative means for presenting a status display.

The display **3010** may preferably be used to display status. In FIGS. **21** to **23**, the second display **3020** is shown.

The second display **3020** may communicate directly with the computer **1010**, or communicating through one of the Network Interface Circuits (NICs).

The second display **3020** may preferably be a Liquid Crystal display. However, one skilled in the art will recognize that there are many alternative means for presenting a status display.

The second display **3020** may preferably be used to display command options, which may be available to an operator of the container handler **78**.

A second display **3020** may also be used in the status reporting device **800** for a UTR truck **10**.

In such situations, when the second display **3020** is present, the status reporting device **800** further includes a network interface circuit supporting a version of the IEEE 802.11 access scheme **2134**.

The operator can receive messages as to where to go in the terminal yard to pickup a container **2**.

The network interface circuit's support of the version of the IEEE 802.11 access scheme **2134**, makes remote reprogramming of the status reporting device **800** possible.

FIGS. **17**, **18**, **21**, **22**, and **24** shows status reporting devices **800** including a second Network Interface Circuit **1034**.

A second network interface coupling **1036** supports the computer **1010** communicating via the second network interface circuit **1034**.

The network interface circuit **1030** and the second network interface circuit **1034** may preferably support distinct serial communications protocols.

By way of example, the network interface circuit **1030** may support RS-232, while the second network interface circuit **1034** may support Ethernet.

Both the network interface circuit **1030** and the second network interface circuit **1034** may preferably be implemented as components within a micro-controller, which also contains the computer **1010**.

The status reporting device **800**, including and its one or more communications protocols may support use of a TCP/IP stack, HTTP, java, and/or XML.

The preceding embodiments have been provided by way of example and are not meant to constrain the scope of the following claims.

What is claimed is:

1. A method for determining a status of a container handler configured to move a container of at least 20 feet in length, comprising:
  - receiving data from a plurality of sensors deployed proximate the container handler to determine one or more states of the container handler;
  - receiving data of the one or more states from the plurality of sensors in a microcontroller module configured to provide at least one member of a crane state list specifying a configuration of a structure element of the container handler to generate a sensed state of the container handler;
  - receiving at least one of global positioning system (GPS) data or radio location tag data for the container handler to determine a location of the container handler;
  - wirelessly transmitting from the microcontroller module the sensed state and the GPS data for the container handler to a computer of a terminal operating system for determination of a location and state of the container handler.
2. The method of claim 1 further comprising:
  - receiving a container code of a container handled by the container handler from an optical character recognition (OCR) component configured to sense the container code to provide an optical container characteristic, and wherein the optical container characteristic includes at least one instance of a member of a container code characteristic list; and wherein the container code characteristic list includes a container code text, a view of the container code, and a compression of the view of the container code; and
  - using the container code and the location of the container handler to determine the location and a state of the container, wherein the optical character recognition module comprises at least one video camera to create at least one instance of the view of the container code and the compression of the view of the container code.
3. The method of claim 2 wherein the container handler is selected from the group consisting of: a utility truck, a gantry crane, a quay crane, a side picker, a reach stacker, a top handler, a straddle carrier, and a chassis rotator.
4. The method of claim 2 wherein plurality of sensors comprise a sensor component configured to sense at least one of an operator identity to provide a sensed operator identity, and a location of the container handler relative to a deployment area, the location determined using at least one of global positioning system data, differential global positioning system data, and timing signals from multiple antenna sites.
5. The method of claim 2 wherein the sensor component is configured to sense a presence of the container to provide a sensed container present status, and wherein the sensed container present status can be used in part to derive a location of the container relative to the container handler.
6. The method of claim 2 wherein microcontroller includes a wireless communication component for wirelessly transmitting, the wireless communication component comprises at least one of a radio-location tag unit and a wireless modem, and includes a network interface circuit supporting at least one wireline communications protocol, the wireline communications protocol supporting a serial protocol selected from the group consisting of: Synchronous Serial interface protocol, Ethernet protocol, Serial Peripheral interface, RS-232 interface, Inter-IC protocol, Universal Serial Bus protocol, Controller Area Network protocol, Firewire protocol, RS-485 protocol, and RS-422 protocol.

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7. The method of claim 1 wherein the crane state list comprises information regarding at least one of a twistlock sensed state, a spreader sensed state, a sensed landing state, a trolley sensed position, and a hoist height.

8. A method for determining the status of a container handler, comprising:

receiving data from a microcontroller controlled by a processor executing program instructions;

receiving data from a sensing component coupled to the microcontroller and configured to sense a state of the container handler and to provide at least one member of a crane state list specifying a configuration of a structure element of the container handler to create a sensed state of the container handler with respect to a characteristic of at least one of a container handler operator and a container manipulated by the container handler, wherein the characteristic of the container manipulated by the container handler comprises a location of the container relative to the container handler as derived from the sensed state of the container handler;

providing a wireless communication component coupled to the microcontroller and configured to transmit the sensed state of the container handler, the wireless communication module using a serial wireless communications protocol and a wireless modulation-demodulation scheme; and

accessing a memory coupled to the microcontroller and storing the program instructions to control the sensing component and the wireless communication component.

9. The method of claim 8 wherein the container handler comprises a human operated device that moves the container within a deployment area, and is selected from the group consisting of: a utility truck, a gantry crane, a quay crane, a side picker, a reach stacker, a top handler, a straddle carrier, and a chassis rotator.

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10. The method of claim 9 further comprising a location determination component configured to wirelessly determine a location of the container handler relative to the deployment area, wherein the location is provided by one of: a Global Positioning System, a Differential Global Positioning System, and timing signals from multiple antenna sites, and wherein the wireless communication component comprises one of: a radio-location tag unit supporting a defined radio communication standard, and a wireless modem.

11. The method of claim 8 wherein the sensing component is selected from the group consisting of: an operator identity sensor, a container presence sensor, an optical container code sensor, a radio frequency tag sensor, a container stack height sensor, a container size sensor, a container weight sensor, a container size sensor, a fuel level sensor, a fifth wheel engage/disengage proximity sensor, and a container damage sensor.

12. The method of claim 8 wherein the sensing component comprises at least one of: a container size sensor including an ultrasonic sonar sensor configured to detect the presence of the container in the container handler, and a distance to the container relative to boundaries of the container handler, and a sensor configured to sense characteristics of a spreader used to grasp the container, the spreader characteristics including a foot-width spread of the spreader selected from one of twenty foot, forty foot, and forty-five foot.

13. The method of claim 8 wherein the sensing component comprises sensors to sense characteristics of a vehicle used to move the container, the vehicle characteristics including fuel level, mileage, operational life, compass reading, reverse motion, and vehicle speed.

14. The method of claim 13 wherein the sensing component comprises sensors to sense a height of a stack of one or more containers relative to the container handler, the stack height sensor including one of: a draw wire encoder and a hollow shaft encoder.

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